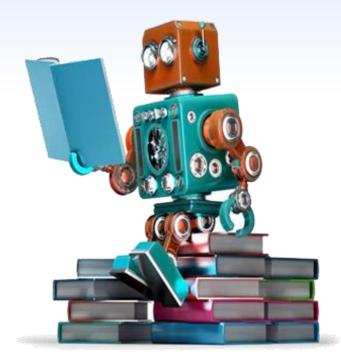


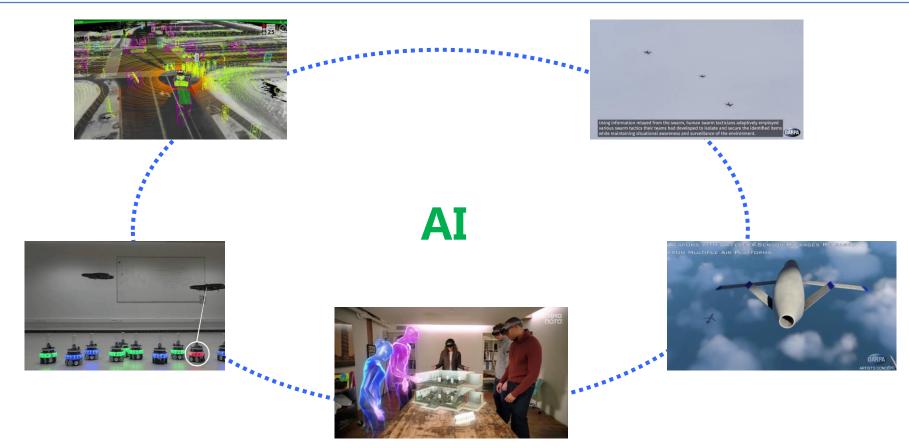
机器学习 Machine Learning















- Small, cheap
- No pilot
- Convenient
- Strong survivability

- Aerial photograph
- Attack
- Air platformGeneral aviation











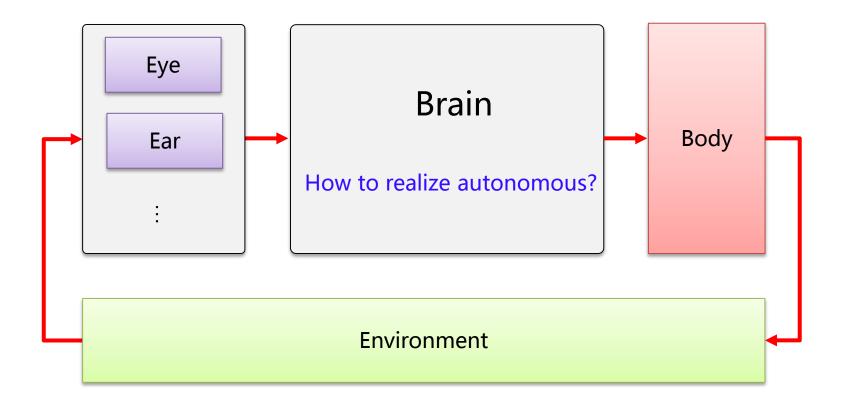




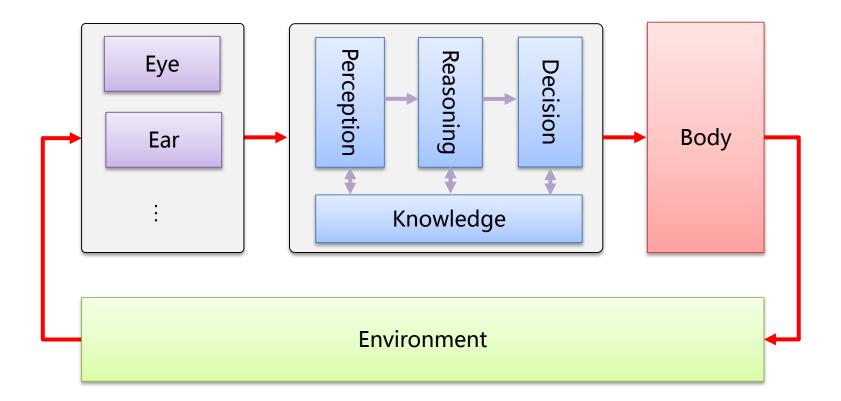






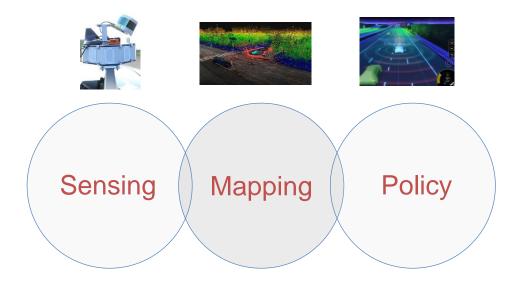






New Challenges



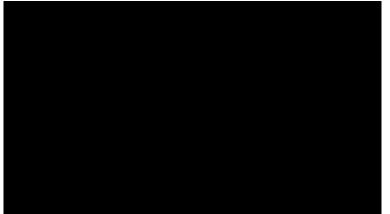


- Multi-type sensors: IMU, GPS, Image, LiDAR, RADAR ...
- High quality and real-time speed required
- Reasoning and knowledge are important for realizing strong AI

Applications





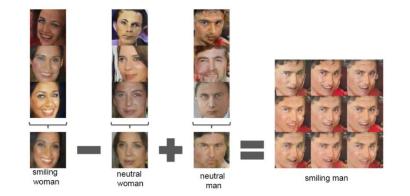


Applications











input



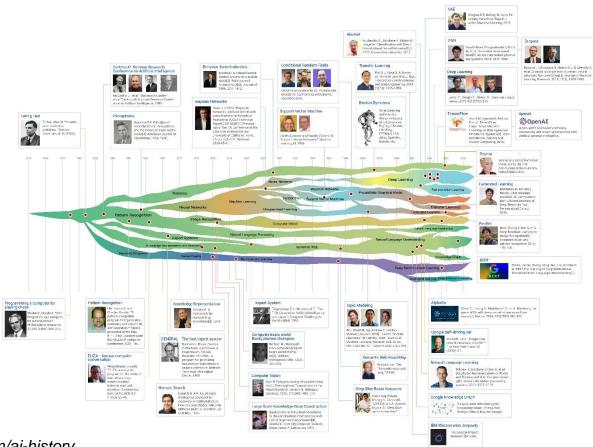
Applications





History of AI





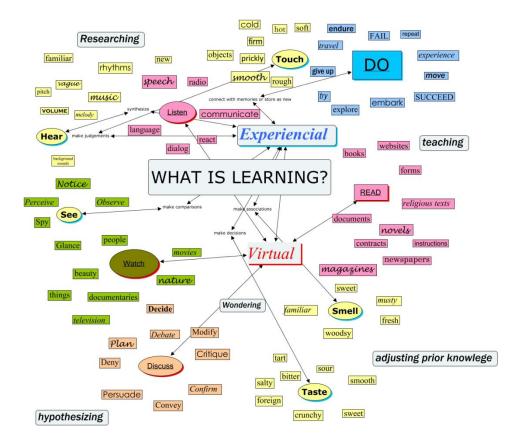
https://www.aminer.cn/ai-history



How to Achieve Intelligence?

How to Achieve Intelligence?





Learning is about seeking a predictive and/or executable understanding of natural/artificial subjects phenomena or activities from ...



Machine learning seeks to develop theories and computer systems for

- Representing
- Classifying, clustering, recognizing
- Reasoning under uncertainty
- Predicting
- And reacting to
- ...

Complex, real world data, based on the system's own experience with data, and (hopefully) under a unified model or mathematical framework, that

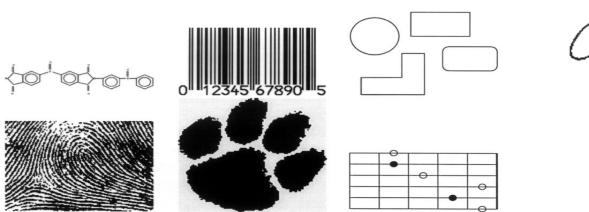
- Can be formally characterized and analyzed
- Can take into account human prior knowledge
- Can generalize and adapt across data and domains
- Can operate automatically and autonomously
- And can be interpreted and perceived by human





"A pattern is the opposite of a chaos; it is an entity vaguely defined, that could be given a name."

- Watanabe



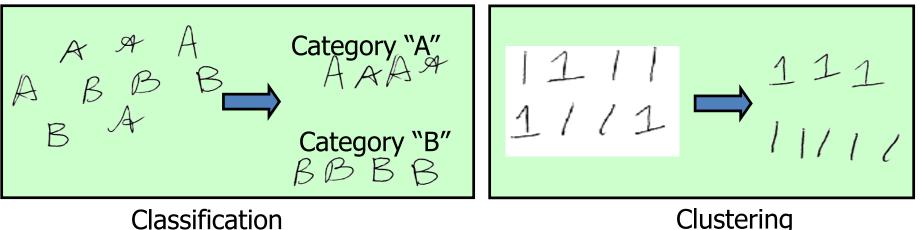


Recognition



Identification of a pattern as a member of a category we already know, or we are familiar with

- Classification (known categories)
- **Clustering** (learning categories)

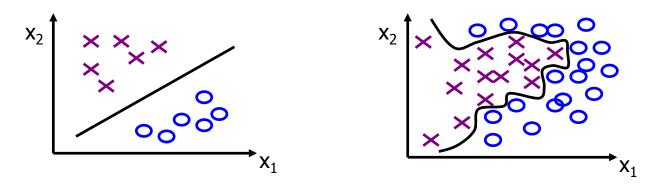


Classification





- Each pattern is represented as a point in *d*-dimensional feature space
- Choice of features and their desired invariance properties are domain-specific



 Good representation implies (i) small intra-class variation, (ii) large inter-class separation and (iii) simple decision boundary



- A collection of similar (not necessarily identical) objects
- A class is defined by class samples (paradigms, exemplars, prototypes, training/learning samples)
- Intra-class variability
- Inter-class similarity
- How do we define similarity?

Intra-class Variability





The letter "T" in different typefaces

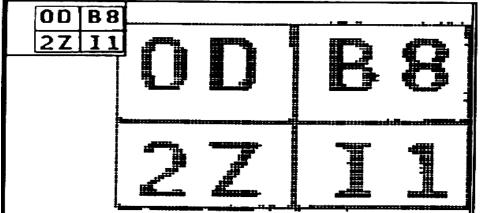


Same face under different expression, pose, illumination

Inter-class Similarity







Identical twins

Characters that look similar

Inter-class or Intra-class?







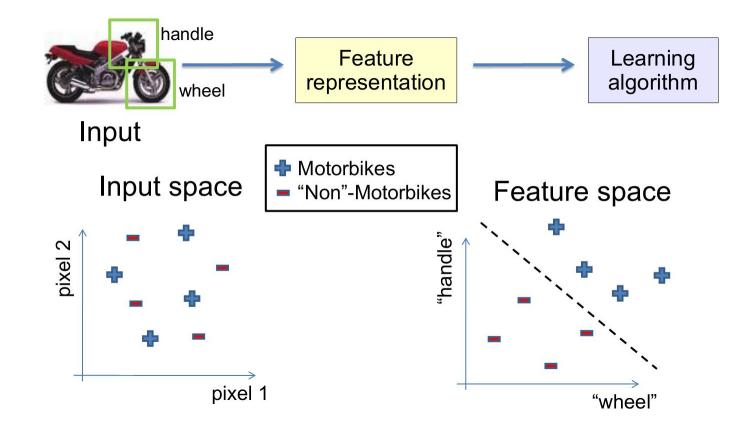


Good Representation

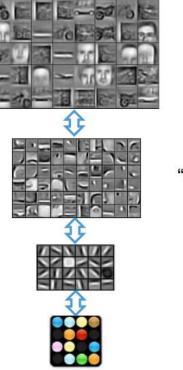
- Should have some invariant properties (e.g., rotation, translation, scale, ...)
- Account for intra-class variations
- Ability to discriminate pattern classes of interest
- Robustness to noise, occlusion,...
- Lead to simple decision making strategies (e.g., linear decision boundary)
- Low measurement cost; real-time

Good Representation







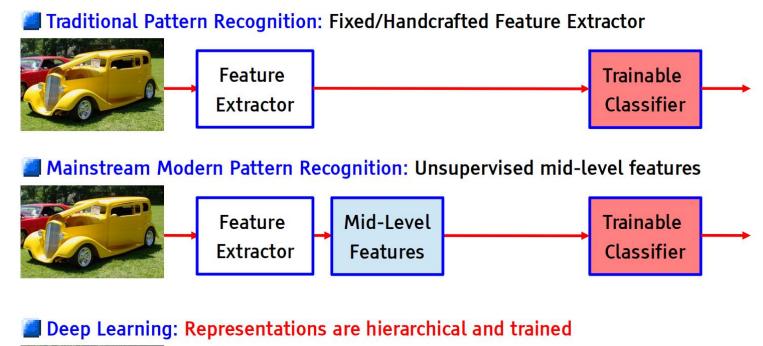


3rd layer "Objects"

- 2nd layer "Object parts"
 - 1st layer "edges"
 - Input

- Represent objects from lowlevel to high-level structure
- Can share the low-level representation for multiple tasks



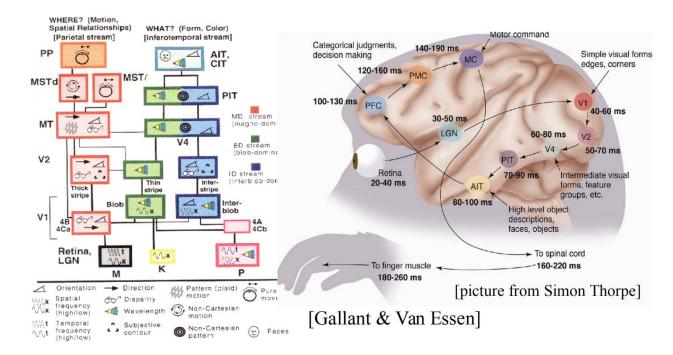




The Mammalian Visual Cortex is Hierarchical

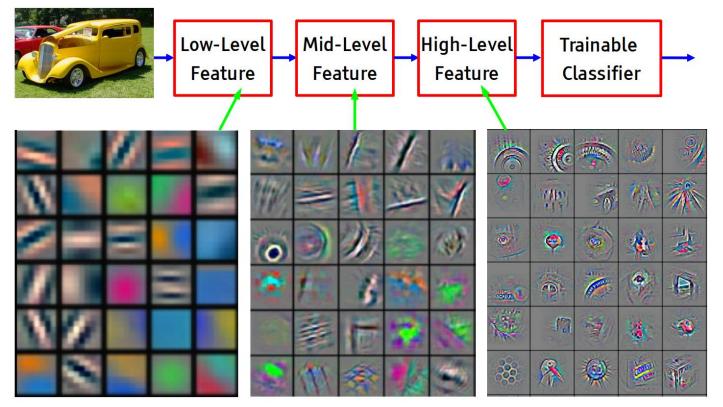


- The ventral (recognition) pathway in the visual cortex has multiple stages
- Retina LGN V1 V2 V4 PIT AIT
- Lots of intermediate representations





It's deep if it has more than one stage of non-linear feature transformation

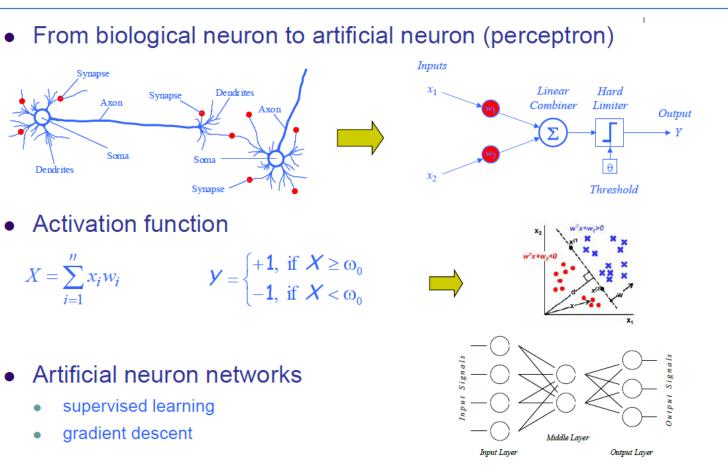




Neural Networks and Deep Learning

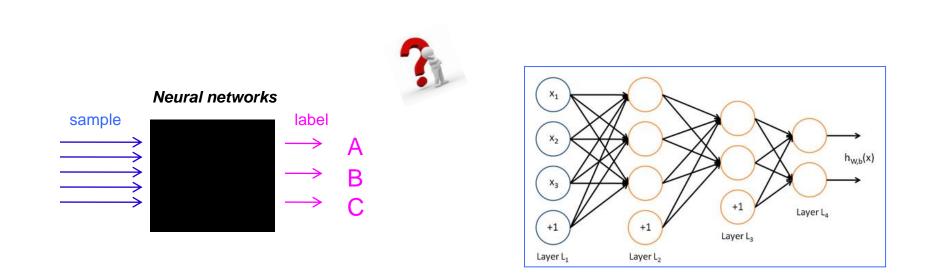
Perceptron and Neural Networks





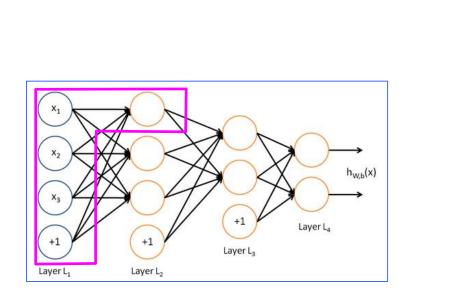
Neural Networks

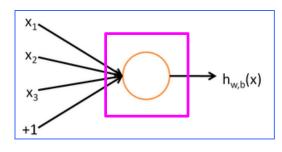


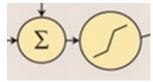


Neural Networks - Feedforward Networks









$$h_{W,b}(x) = f(W^T x) = f(\sum_{i=1}^3 W_i x_i + b)$$
$$f(z) = \frac{1}{1 + \exp(-z)}$$

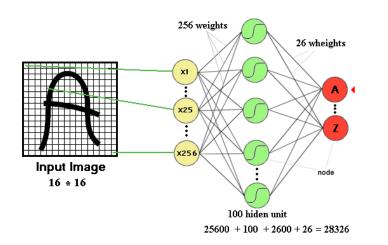
Neural Networks - Feedforward Networks

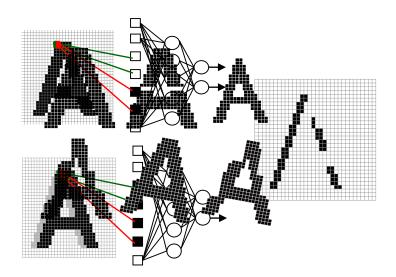




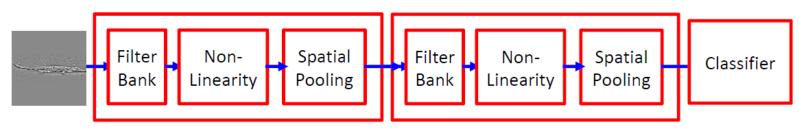


- The number of trainable parameters becomes extremely large
- Little or no invariance to shifting, scaling, and other forms of distortion





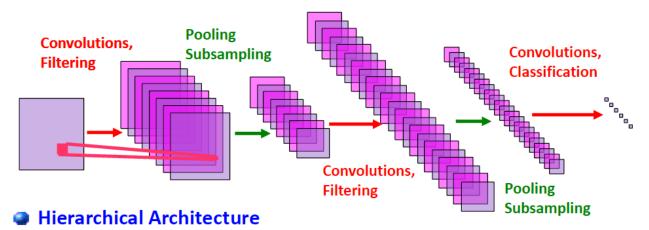




- Multiple Stages
- Each Stage is composed of
 - A bank of local filters (convolutions)
 - A non-linear layer (may include harsh non-linearities, such as rectification, contrast normalization, etc...).
 - A feature pooling layer
- Multiple stages can be stacked to produce high-level representations
 - Each stage makes the representation more global, and more invariant
- The systems can be trained with a combination of unsupervised and supervised methods

Convolutional Neural Network: Multi-stage Trainable Architecture





Representations are more global, more invariant, and more abstract as we go up the layers

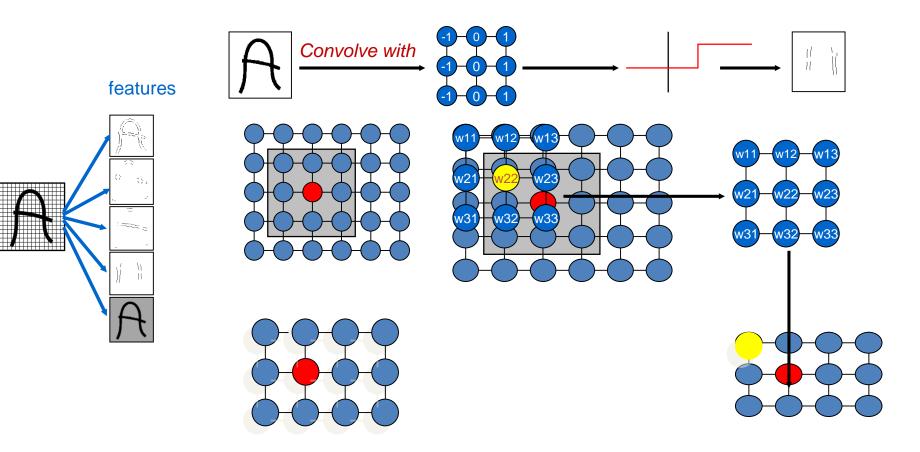
Alternated Layers of Filtering and Spatial Pooling

- Filtering detects conjunctions of features
- Pooling computes local disjunctions of features

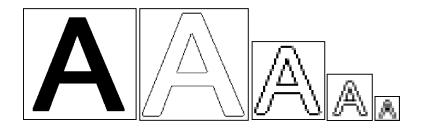
Fully Trainable

All the layers are trainable

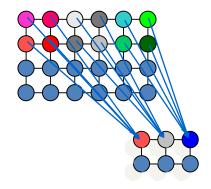








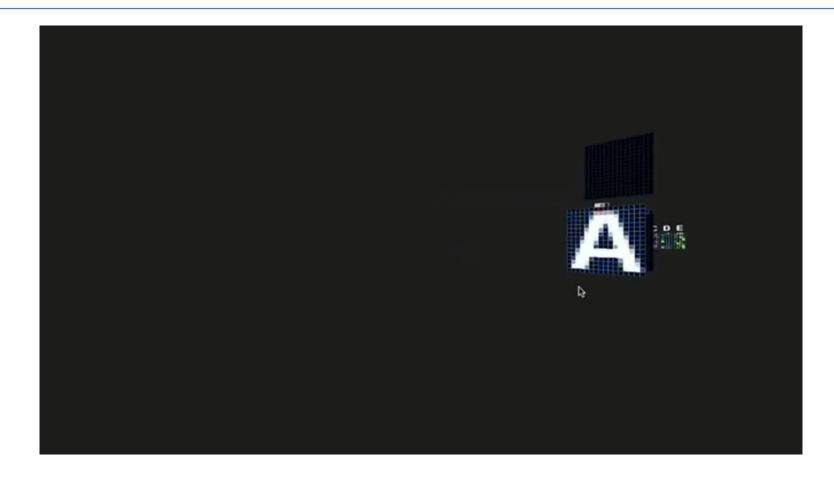




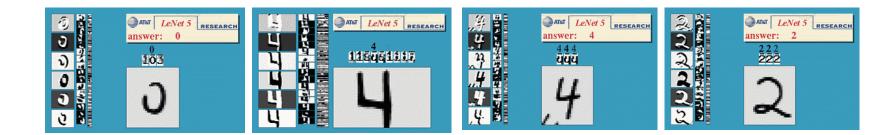
- By reducing the spatial resolution of the feature map, reduce the effect of noises and shift or distortion.
- The weight sharing is also applied in subsampling layers

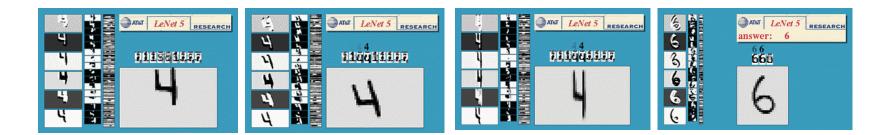
Convolutional Neural Networks - Demo







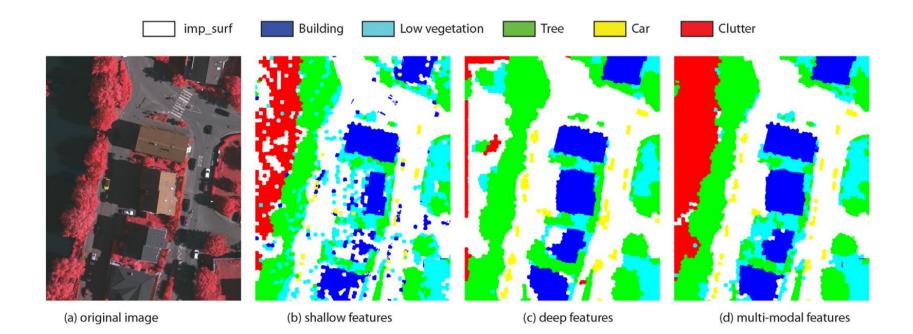






Applications

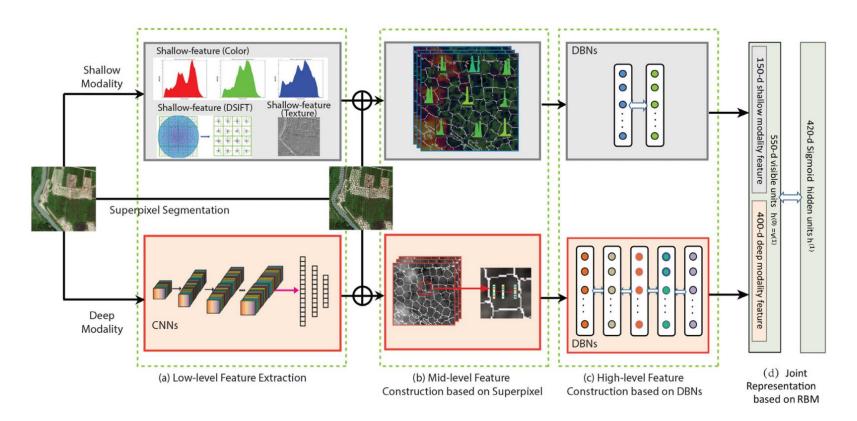




Ke Li, et al. Multi-modal feature fusion for geographic image annotation

Application (1) Image Annotation

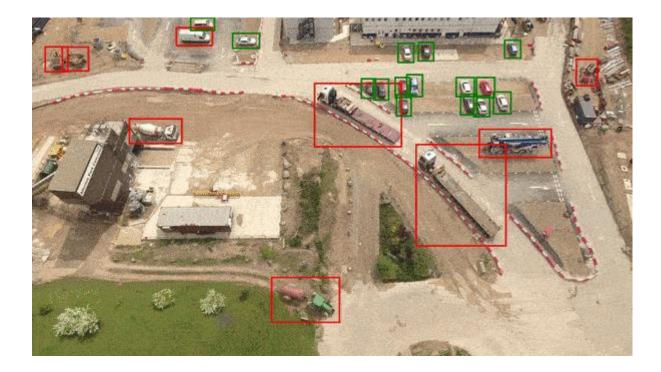




Ke Li, et al. Multi-modal feature fusion for geographic image annotation

Application (2) Object Detection

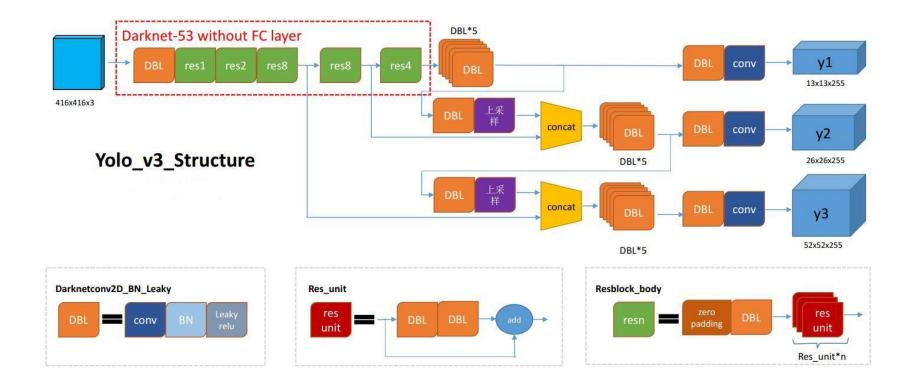




Joseph Redmon, et al. YOLOv3: An Incremental Improvement

Application (2) Object Detection





Joseph Redmon, et al. YOLOv3: An Incremental Improvement

Application (3) Deep Learning based SLAM



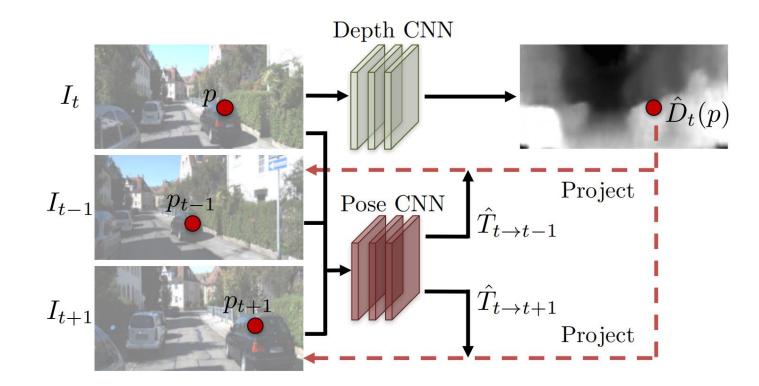


Estimate position and depth image simultaneously

Tinghui Zhou, et al., Unsupervised Learning of Depth and Ego-Motion from Video

Application (3) Deep Learning based SLAM





Tinghui Zhou, et al., Unsupervised Learning of Depth and Ego-Motion from Video

Application (4) Place Recognition





















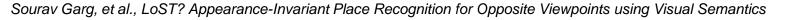






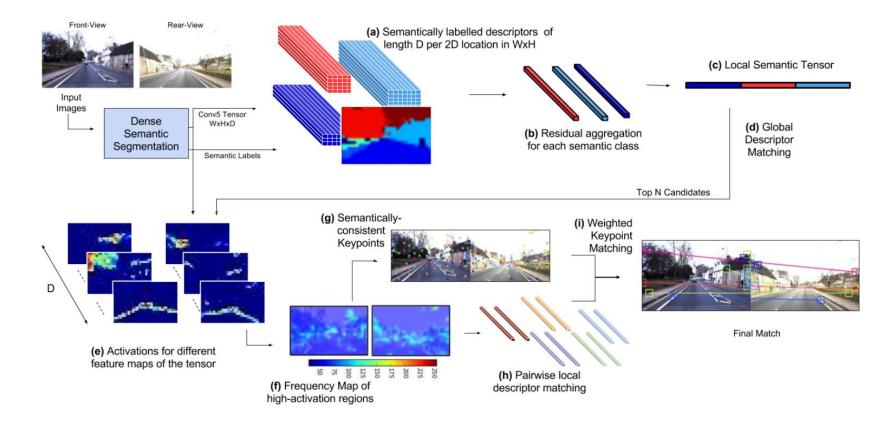






Application (4) Place Recognition



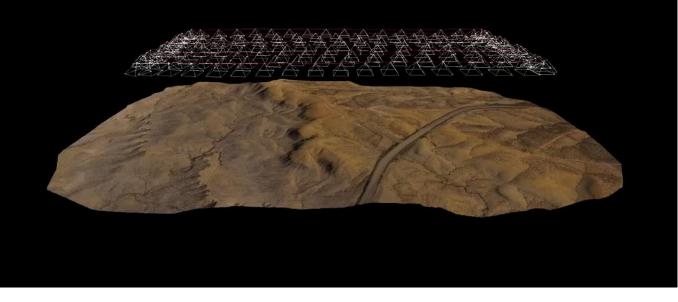


Sourav Garg, et al., LoST? Appearance-Invariant Place Recognition for Opposite Viewpoints using Visual Semantics

Application (5) Realtime 3D Map

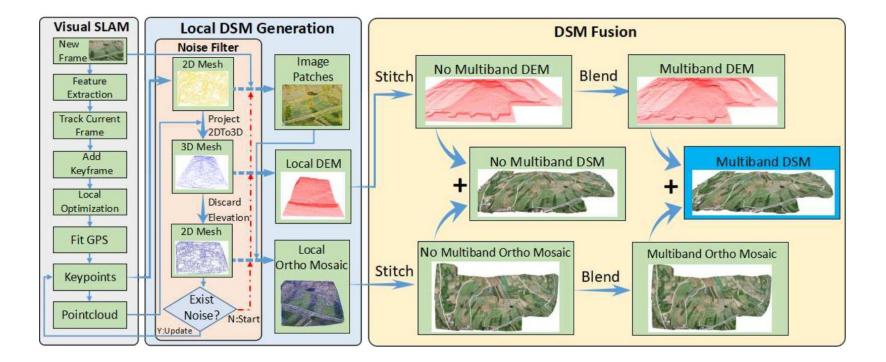


TerrainFusion: Real-time Digital Surface Model Reconstruction based on Monocular SLAM



Wei Wang, et al., TerrainFusion: Real-time Digital Surface Model Reconstruction based on Monocular SLAM

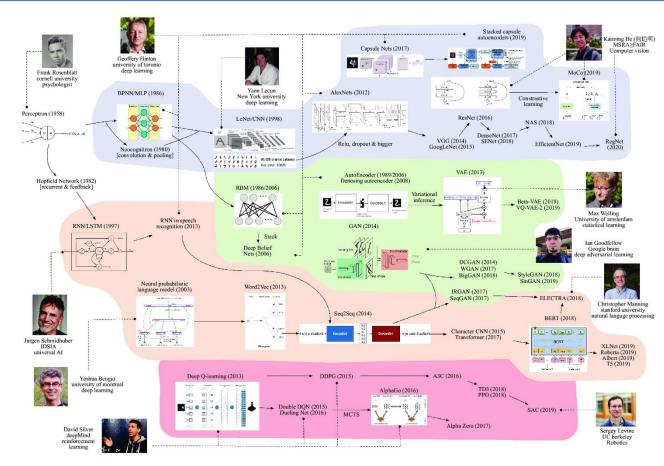




Wei Wang, et al., TerrainFusion: Real-time Digital Surface Model Reconstruction based on Monocular SLAM

Summary - Methods



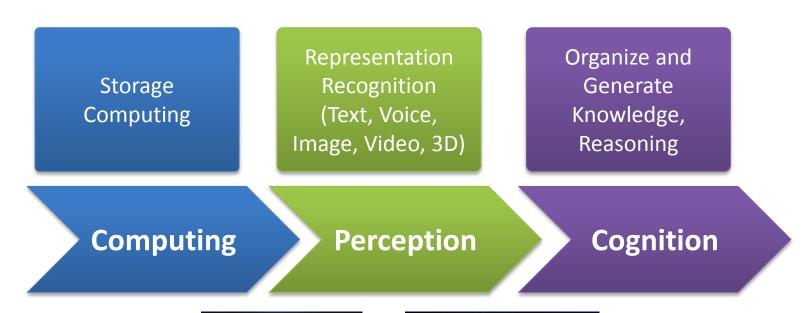


Summary - Problems



- General-purpose intelligent system is a very difficult problem
- Successful systems available in well-constrained domains
- All components are coupled
- No single approach has been found to be optimal for all problems
- Use of object models, constraints and context is necessary for identifying complex patterns
- Careful sensor design and feature extraction often lead to simple classifiers



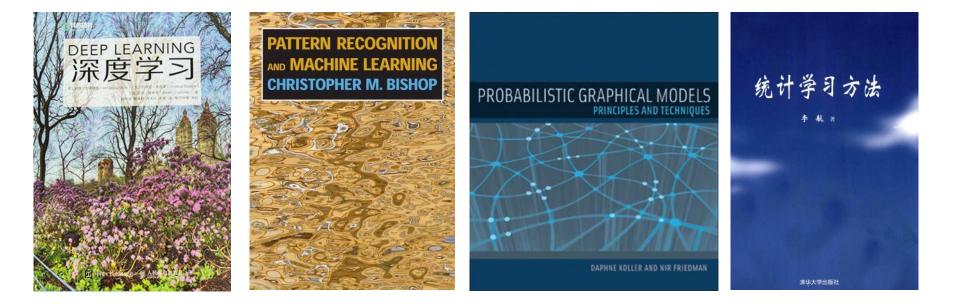






Books







Notebook: <u>https://gitee.com/pi-lab/machinelearning_notebook</u> Homework: <u>https://gitee.com/pi-lab/machinelearning_homework</u>





THANK YOU

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