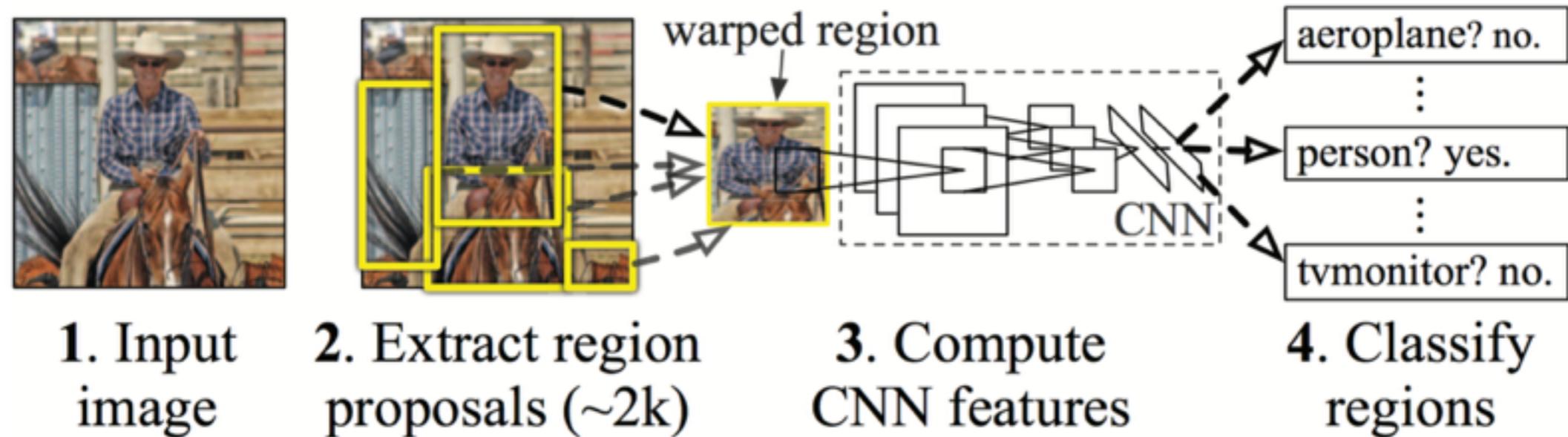


Visual Attention With Neural Networks

Main Paper: Recurrent Models of Visual Attention

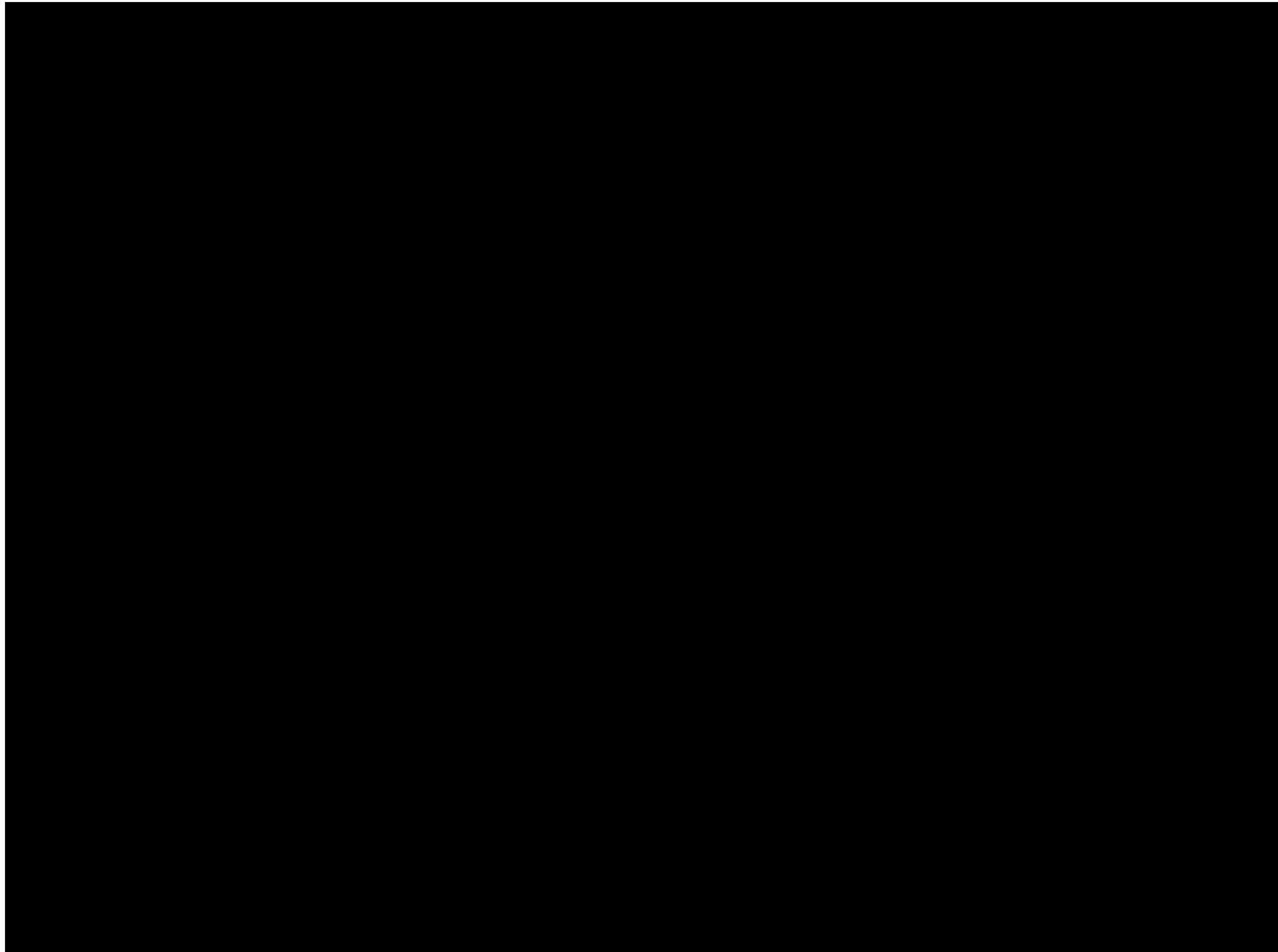
Presentation by Matthew Shepherd

Full image processing is computationally expensive



Regions are can be selected intelligently but time still scales with the size of the image

Humans focus on specific
regions in their FOV

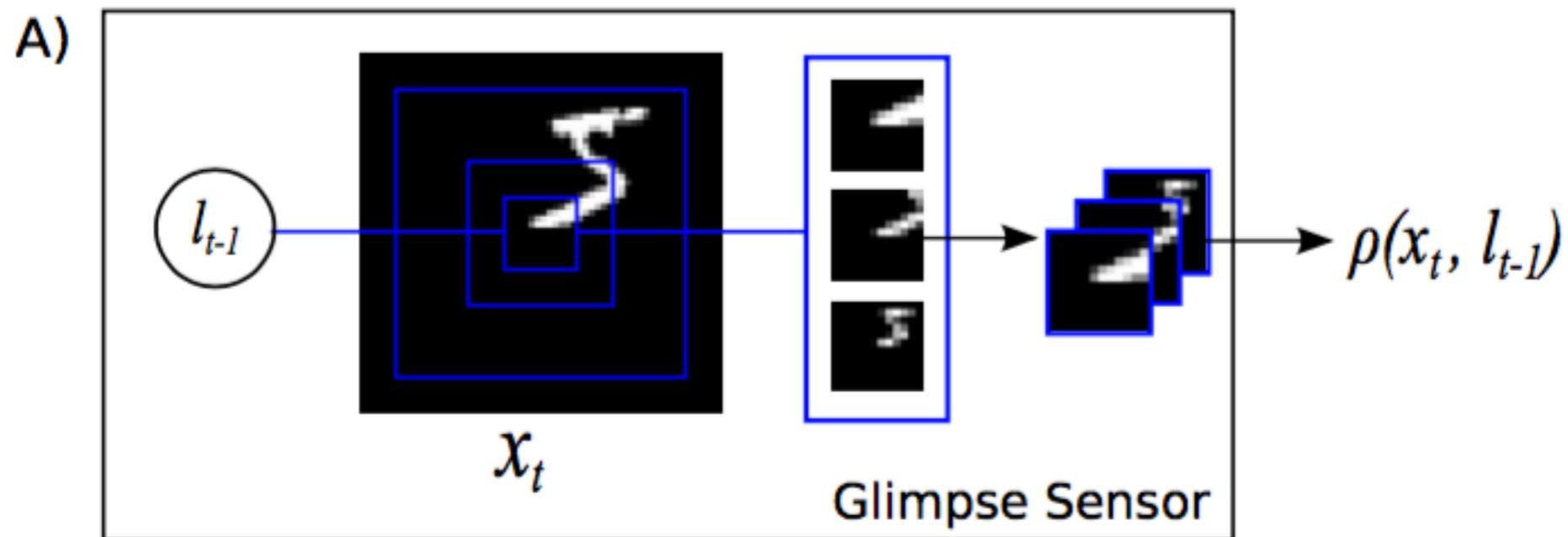


“Vision as a sequential decision task”

The model sequentially chooses small windows of information on the data

Integrates information from all past windows to make its next decision.

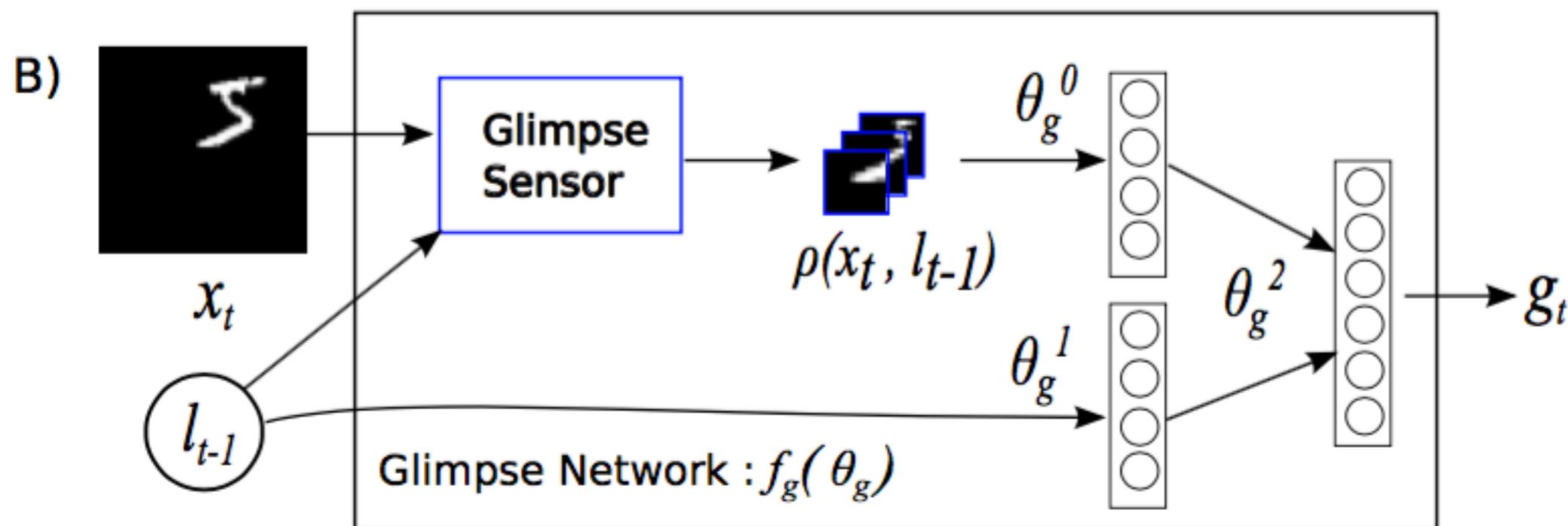
The sensor only provides limited information about the scene, X_t , focused at a location, l_{t-1}



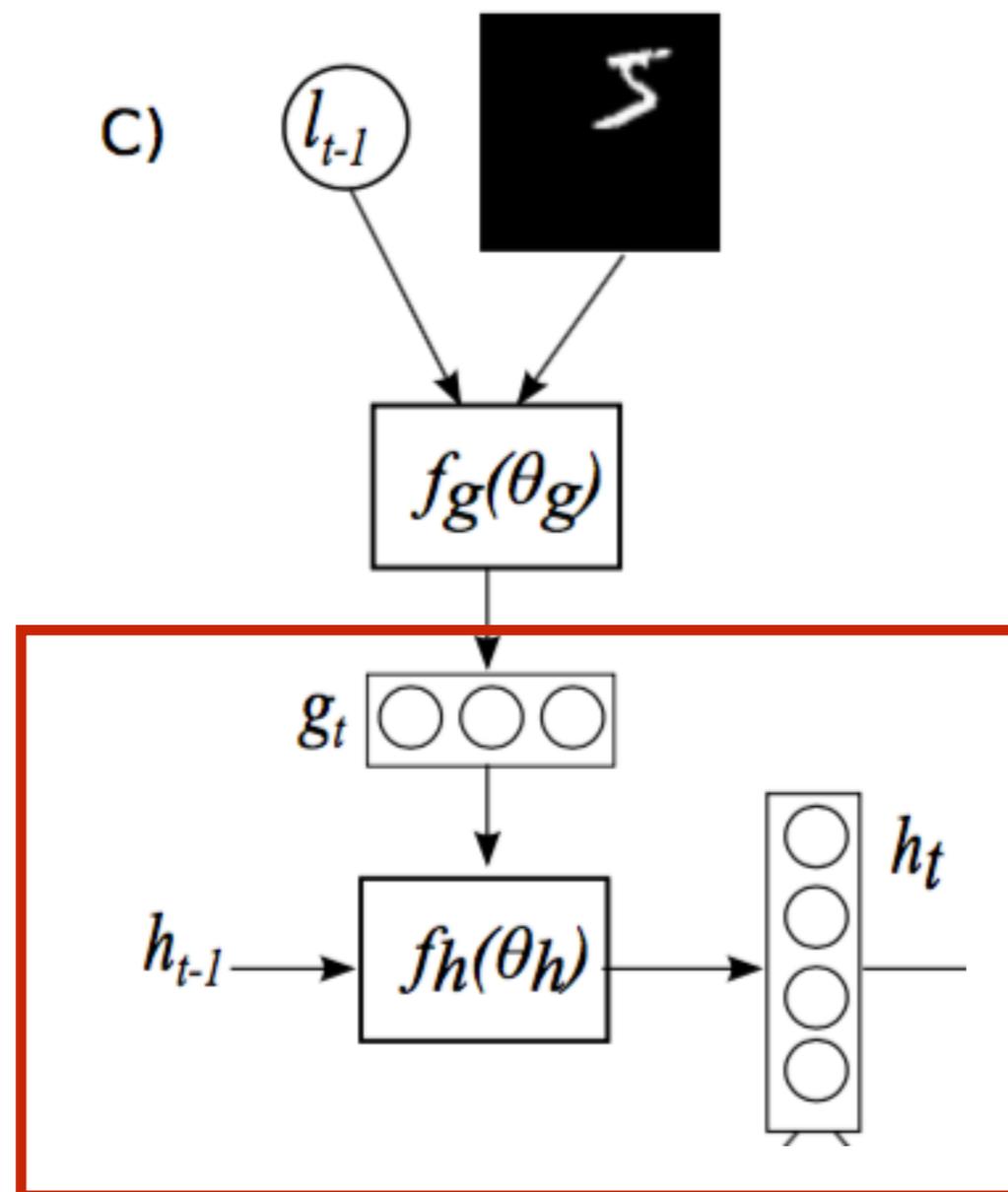
Referred to as a
"Glimpse"

retina-like
representation

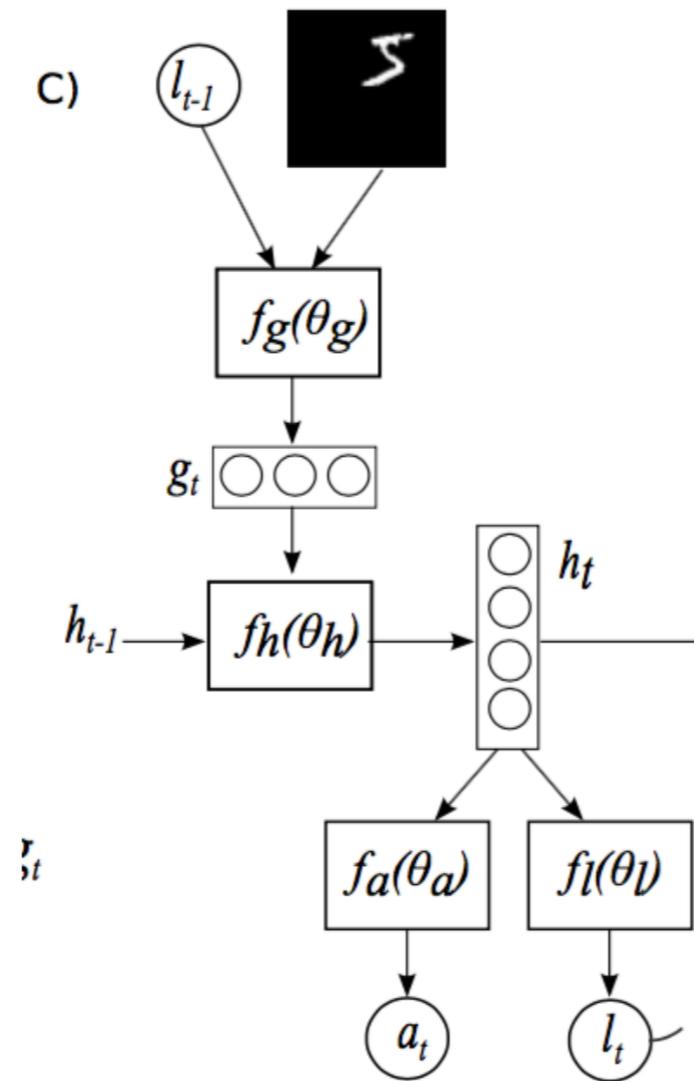
The “glimpse network” incorporates sensor and location information into a single vector



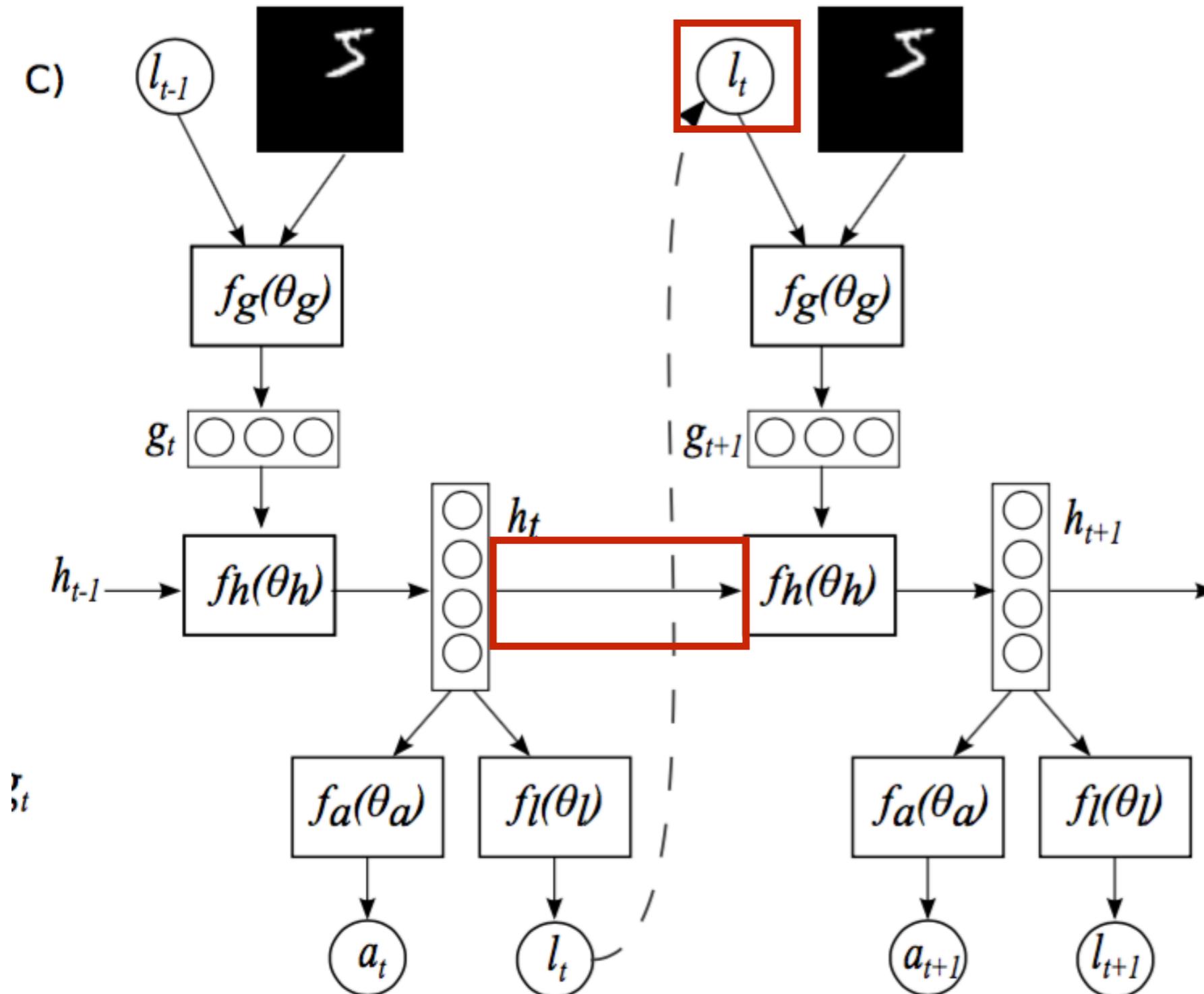
The core network $f_h(\theta_h)$ incorporates the sensor information as well as past information



The output of the core network is then used to deploy the sensor and make a classification



The network is recurrent



Partially Observed Markov Decision Problem (POMDP)

- Glimpse can be seen as a partial view of the state
- Network must learn a policy

$$\pi((\mathbf{l}_t, \mathbf{a}_t) | \mathbf{s}_{1:t}; \theta)$$

- The policy is determined by the NN
- State history is encapsulated by the hidden state of the network

So how do we train it?

$$J(\theta) = \mathbb{E}_{p(s_{1:T};\theta)} \left[\sum r_t \right]$$

$$\nabla_{\theta} J = \sum_{t=1}^T \mathbb{E}_{p(s_{1:T};\theta)} [\nabla_{\theta} \log \pi(u_t | s_{1:t}; \theta) R] \approx \frac{1}{M} \sum_{i=1}^M \sum_{t=1}^T \nabla_{\theta} \log \pi(u_t^i | s_{1:t}^i; \theta) R^i$$

The REINFORCE rule

Additional training details

Useful for determining f_l but f_a can be determined more directly by minimizing cross-entropy loss.

A baseline value, b_t , is added to the gradient approximation to reduce variance

$$\frac{1}{M} \sum_{i=1}^M \sum_{t=1}^T \nabla_{\theta} \log \pi(u_t^i | s_{1:t}^i; \theta) (R_t^i - b_t)$$

Experiments

RAM performs well on translated MNIST



Model	Error
FC, 2 layers (64 hidden each)	6.42%
FC, 2 layers (256 hidden each)	2.63%
Convolutional, 2 layers	1.62%
RAM, 4 glimpses, 12×12 , 3 scales	1.54%
RAM, 6 glimpses, 12×12 , 3 scales	1.22%
RAM, 8 glimpses, 12×12 , 3 scales	1.2%

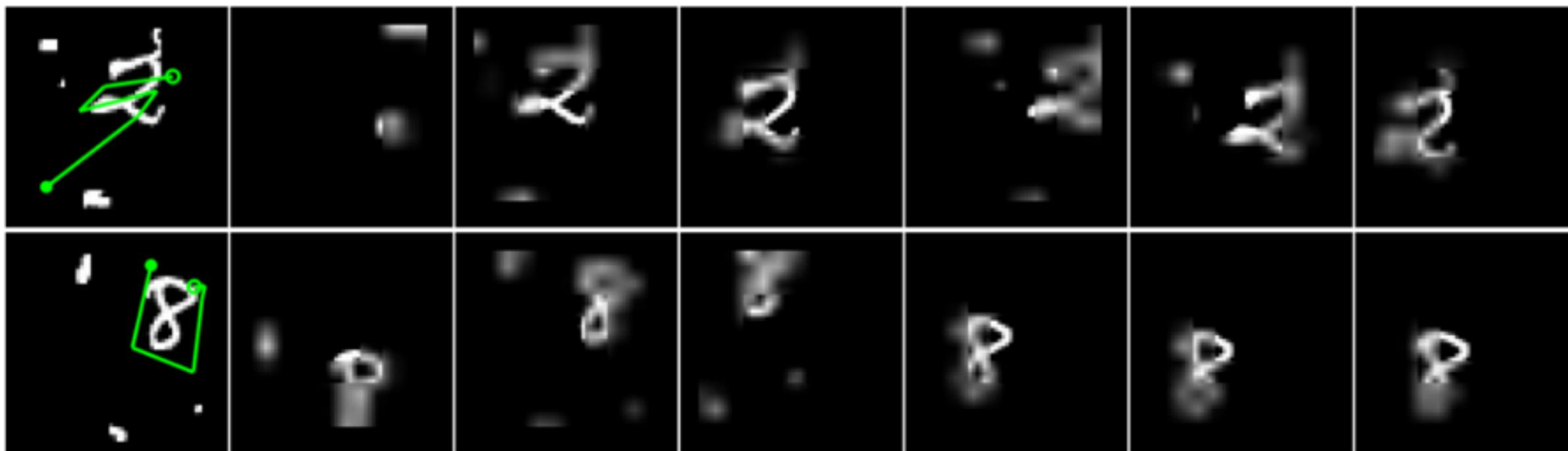
RAM performs very well on cluttered translated images



(b) 100x100 Cluttered Translated MNIST

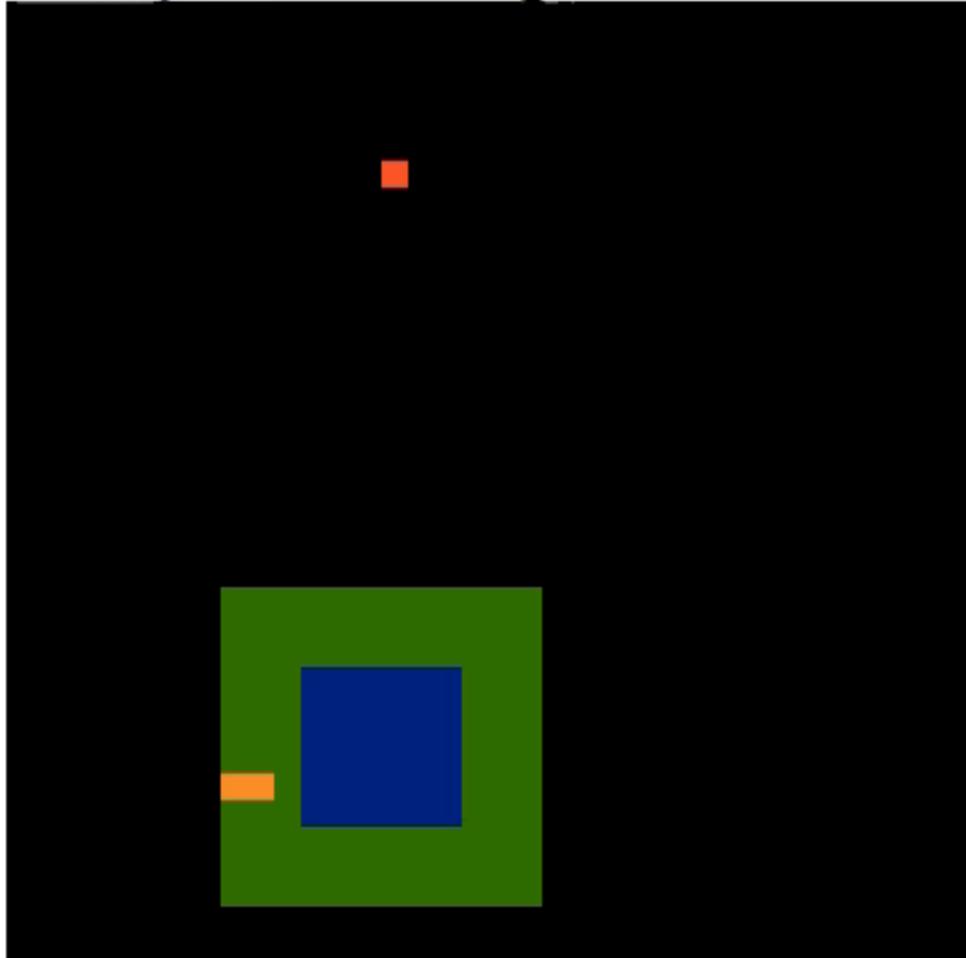
Model	Error
Convolutional, 2 layers	14.35%
RAM, 4 glimpses, 12×12 , 4 scales	9.41%
RAM, 6 glimpses, 12×12 , 4 scales	8.31%
RAM, 8 glimpses, 12×12 , 4 scales	8.11%
RAM, 8 random glimpses	28.4%

Meaningful policies are learned

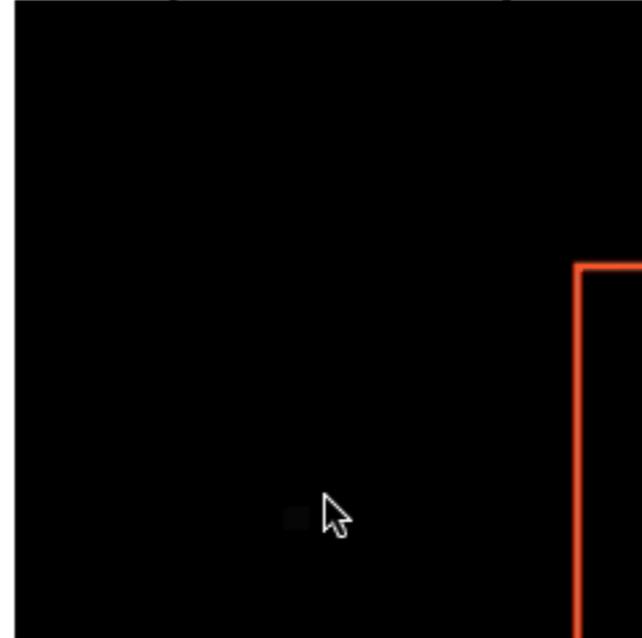


RAM performs in a dynamic environment

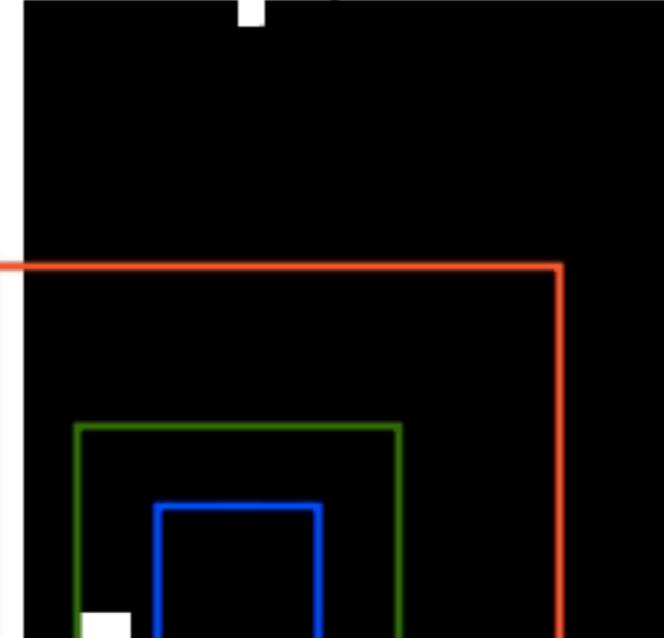
Glimpse Coverage



Glimpse History



Game Play

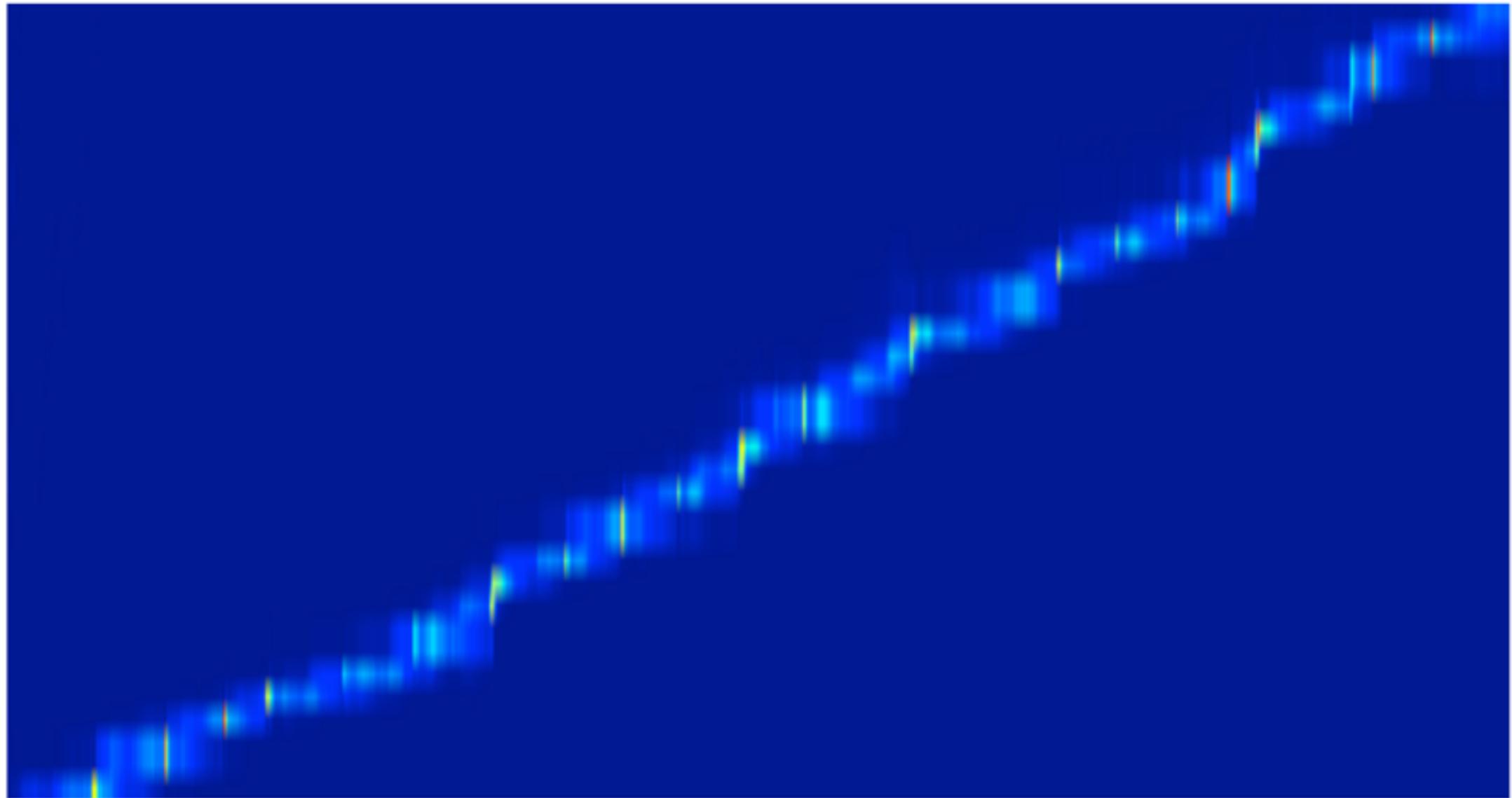


Individual Glimpses



Other models of attention

Thought that the muster from

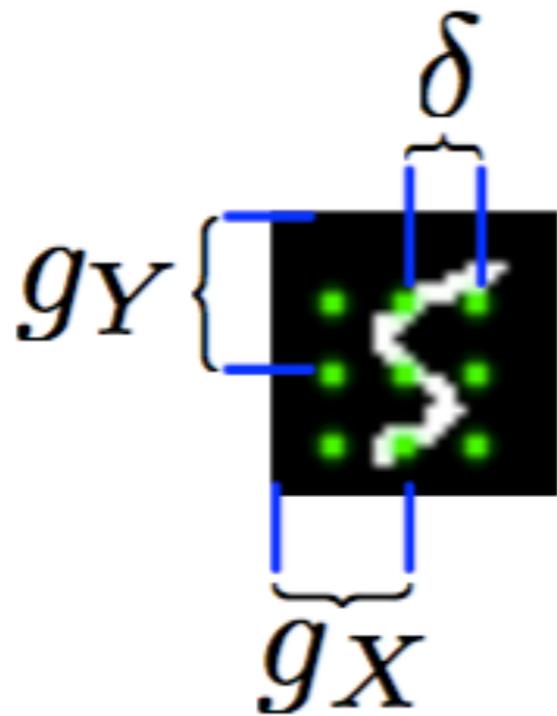


Thought that the muster from

DRAW: A Recurrent Neural Network For Image Generation

- Combines an attention mechanism with a sequential variational auto-encoder
- Reading *and* writing are now both sequential tasks

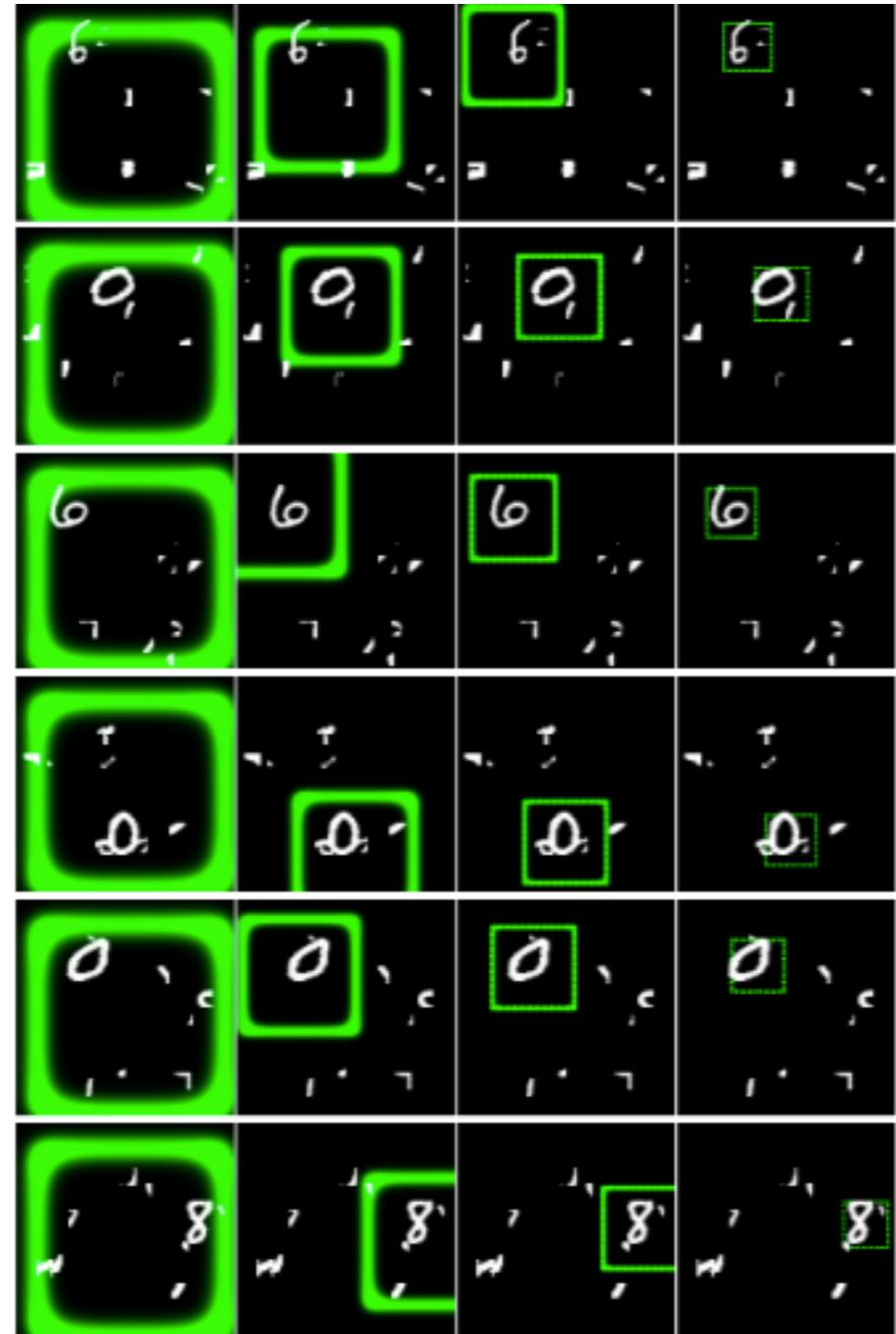
Differentiable RAM



$$\mu_X^i = g_X + (i - N/2 - 0.5) \delta$$

$$\mu_Y^j = g_Y + (j - N/2 - 0.5) \delta$$

$$(\tilde{g}_X, \tilde{g}_Y, \log \sigma^2, \log \tilde{\delta}, \log \gamma) = W(h^{dec})$$



Differentiable RAM performance

Table 1. Classification test error on 100×100 Cluttered Translated MNIST.

Model	Error
Convolutional, 2 layers	14.35%
RAM, 4 glimpses, 12×12 , 4 scales	9.41%
RAM, 8 glimpses, 12×12 , 4 scales	8.11%
Differentiable RAM, 4 glimpses, 12×12	4.18%
Differentiable RAM, 8 glimpses, 12×12	3.36%

DRAW-ing with attention



Reading MNIST