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Image Classification by Reinforcement Learning with Two- State Q-Learning

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Abstract. In this paper, a simple and efficient Hybrid Classifier is presented which is based on deep learning and reinforcement learning. Q-Learning has been used with two states and 'two or three' actions. Other techniques found in the literature use feature map extracted from Convolutional Neural Networks and use these in the Q-states along with past history. This leads to technical difficulties in these approaches because the number of states is high due to large dimensions of the feature map. Because our technique uses only two Q-states it is straightforward and consequently has much lesser number of optimization parameters, and thus also has a simple reward function. Also, the proposed technique uses novel actions for processing images as compared to other techniques found in literature. The performance of the proposed technique is compared with other recent algorithms like ResNet50, InceptionV3, etc. on popular databases including ImageNet, *Cats and Dogs* Dataset, and Caltech-101 Dataset. Our approach outperforms others techniques on all the datasets used.

Keywords: Image Classification; ImageNet; Q-Learning; Reinforcement Learning; Resnet50; InceptionV3; Deep Learning;

1 Introduction

Reinforcement Learning (RL) [1-4] has garnered much attention [4-13]. In computer vision, good initial work [7,14,15,11,9,5,12,16-20] has been undertaken. In [14], the authors aim to reduce the large computational costs of using large images, by proposing a RL agent which adaptively selects the resolution of every image provided by the detector. They train the agent with double rewards by choosing lower resolution images for a coarse level detector in case of the image being dominated by large objects, and higher resolution images for a fine level detector in case of the image being dominated by small objects. In [20], the authors propose an object

detection technique based on reinforcement Q-learning [21,22]. They use a policy search based on analytic gradient computation with continuous reward. They report almost two orders of magnitude speed-up over other popular techniques found in literature. In [23], an adaptive deep Q-learning technique has been used for improving and shortening computational time for digit recognition. They refer to their novel network as Q-learning deep belief network (Q-ADBN). This network extracts features from a deep auto-encoder [24], which are considered as current states of Q-learning algorithm. After conducting experiments on MNIST dataset [25], the claim that their technique is superior to other techniques in terms of accuracy and running time. In [26], the authors propose an object detection approach which uses zooming and translation for successively refining the bounding box for the objects. They use a VGG-16 Convolutional Neural Network (CNN) [27] and concatenate its feature map with a history vector, and this new map is fed to a Q-network for further processing, leading to interesting results. In [28], the authors propose a technique in which an agent learns to deform a bounding box using simple transformation actions, with the aim of obtaining specific location of objects by following top-down reasoning. The actions used are horizontal moves, vertical moves, scale changes and aspect ratio changes.

Taking a hint from the work in area of Maximum Power Point Tracking (MPPT) which is used in Photovoltaic Arrays[29], we have proposed a simple and efficient technique for image classification which gives high accuracy. It is based on deep learning as well as reinforcement learning. The technique involves using feature maps obtained from the a pre-trained CNN like ResNet50 [30], InceptionV3 [31], or Alexnet [32]. Next, reinforcement learning is used for optimal action proposal generation (rotation by a specific angle or translation) on the image. After application of the final action to the original test image, and obtaining feature map from the CNN [33-36,30,31,37], classification is done using a second classifying structure, like a Support Vector Machine (SVM) [38-40] or a Neural Network (NN) which has been trained on the CNN feature maps of training images.

Many reinforcement learning techniques [20,18,26,28] used for image classification use actions like zoom and translation according to visual detection in humans. Thus they miss the important action of rotating the field of view used in human visual image comprehension. In this paper we use rotation of image by specific angle(s) which is novel in itself. We also use Q-Learning in reinforcement learning. Q-states which have been used in the other approaches of reinforcement learning based object detection, use features with high dimensions combined with state history. This technique usually leads to large state-space, in turn leading to optimization problems. The proposed technique uses only two states, and two or three actions. As a consequence of this strategy, the Q-table has two rows and two/three columns. To the best of our knowledge, this is the first technique using two Q-states, as well as using image rotation as an action. In spite of the simplicity of the proposed technique, better results are obtained in comparison to other techniques involving CNNs like ResNet50 [41,30,37], InceptionV3 [31], etc.

2 Proposed Approach

In this paper a hybrid approach of deep learning [42,7,14,43-46] and Reinforcement Learning (RL) is proposed. The CNNs used are ResNet50 [41,30,37], InceptionV3 [31], and AlexNet [32]. First, feature-map of the CNN is obtained for every training sample by feeding it to the CNN. Let the set of all of these feature maps be referred to as F_{Train} . A secondary classifier like a Support Vector Machine, or a Neural Network is trained on F_{Train} . For classifying a test sample, a filtering criterion for 'hard to classify' samples must be used. If the test sample is tagged as hard, it is classified by reinforcement learning. If not, then CNN is used for classification. This paper is not about filtering criteria, hence no such criterion has been used except that all test samples misclassified by the CNN are tagged as 'hard to classify.' Every 'hard' test sample is first fed to the CNN. Next, the feature map of the CNN, viz. F_{Sample} for the test image is obtained. Reinforcement learning based classification is done as follows. A random action is selected from a bank of actions whose number does not exceed 3 in all the experiments. Next, the action permutation is applied to the test image. Then the new feature map (F'_{Sample}) of the permuted image is obtained from the CNN. The action permutations used in this work are mainly image rotation with specific angles and sometimes diagonal translation. For reinforcement learning, Q-Learning with random policy is used. Two states ($n = 2$) and 'two or three' actions ($a = 2$) or ($a = 3$) are used. The current state is decided after observing a metric viz. 'standard deviation' of the prediction scores (of the second classifier) before and after applying the permutation. Let M be metric for original image and M_1 be metric after applying current action. The new state is decided based on the criteria whether M_1 is lesser than, equal to, or larger than M respectively. The Q Table having 2 rows ($n=2$) and a columns ($a = 2$ or 3) is initialized to zero. Reward r is based on the comparison as shown below:

$$r = \left\{ \begin{array}{ll} +1, & \text{if } M_1 > M \\ 0, & \text{if } M_1 = M \\ -1, & \text{if } M_1 < M \end{array} \right\} \quad (1)$$

Number of iterations for updating the Q Table is $N = a \times m$, where $a=2$ or 3 and m is a constant (usually 20). After each iteration, the Q value entry for the current 'state-action pair' with state s and action a i.e. $Q(s,a)$ present in the Q-Table, is updated as per the Q-Learning Update Rule:

$$Q(s, a) = Q(s, a) + \alpha [r + \gamma \max_{b \in A} Q(s', b) - Q(s, a)] \quad (2)$$

Where s' is new state, the learning rate $\alpha = 0.4$, and the discount rate $\gamma = 0.3$. Flowchart for the proposed RL algorithm is given in Figure 1. After completing N iterations of Q-Learning, optimal action is chosen as the action having highest value in Q-Table. Finally the optimal action is applied to the original sample/test image. Next the image is fed to the CNN giving its feature map. This feature map is fed to the second classifying structure for classification. Figure 2 shows the proposed approach in modular fashion

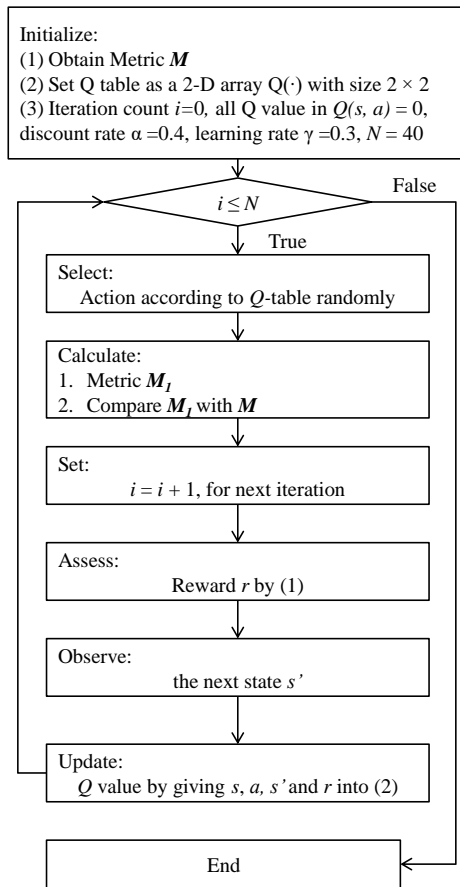


Figure 1. Flowchart of the proposed RL Algorithm

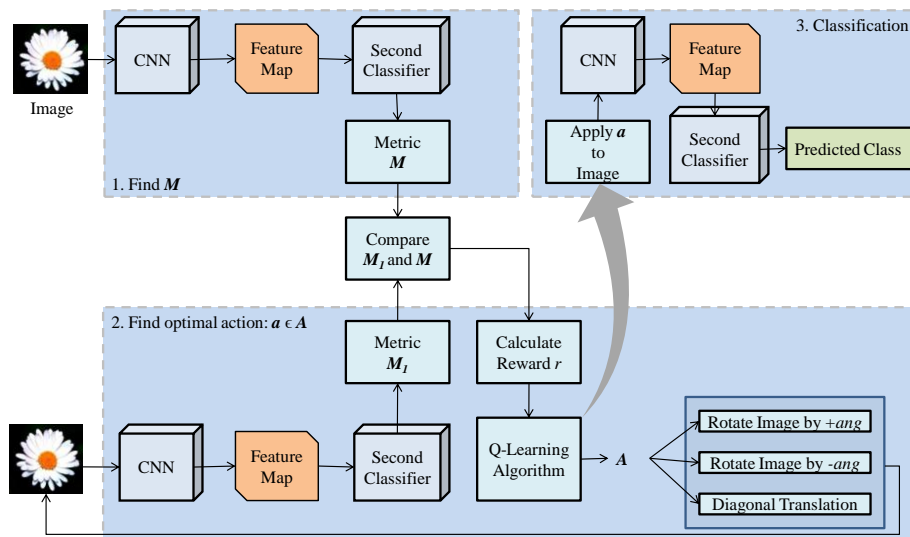


Figure 2. Proposed Technique

The NNs used on top of ResNet50 and InceptionV3 networks are shown in Figure 3(a) and 3(b), respectively.

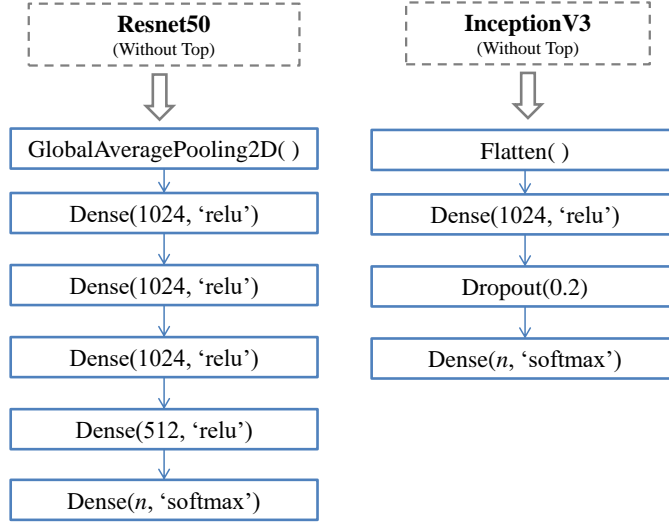


Figure 3. Shown are NNs used after the CNNs, viz. ResNet50 (left), and InceptionV3 (right) which are implemented in Tensorflow without top; n is number of classification categories

3. Experimentation

Experiments were conducted on a machine having an *Intel® Xeon®* processor (with 2 Cores), 12.6 GB RAM and 12 GB GPU. For benchmarking of the performance of the proposed technique, its performance was compared with that of the pre-trained CNN used alone after being fine-tuned on the datasets. Tensorflow [47] has been used for implementing the CNNs (pre-trained, having ImageNet weights) and algorithms. For training the CNNs using transfer learning, 10 *training epochs* were used, with optimizer: *Adam*, Loss: *Categorical Crossentropy*, and Learning Rate: *0.001*. Benchmarking has been done on three popular databases viz. ImageNet [48,49], *Cats and Dogs* Dataset [50], and Caltech-101 Dataset [51]. The distribution of data amongst the experimental setups is shown in Table 1.

Table 1. Distribution of Data Experimentally

Dataset	Classes Used	Training Images	Validation Images	Testing Images
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ImageNet [48]	4 (Bikes, Ships, Tractors, Wagons)	1531	788	745
Cats and Dogs [50]	2 (Cats, Dogs)	2000	500	500
Caltech-101 [52]	50	750	-	1250

Tables 2 to 4 show the benchmarking for the performance of the proposed approach on the datasets used. It should be noted that for Caltech-101 a two action set comprising of angular rotation by 12.5° or by -12.5° gave best results, while as for ImageNet and *Cats and Dogs* Dataset, a three action set comprising of angular rotation by 90° , or by 180° , or *downward and rightward* diagonal translation by 15 pixels gave best results.

Table 2. Classification Accuracy of Various Approaches on ImageNet
(**Second Classifier Used:** NN; **Metric Used:** Std. Deviation of Softmax scores,
Feature Map Size: 1x1024)

Approach	Secondary NN used on top of Layer	Image Size	Accuracy
ResNet50	#174: @(conv5_block3_out)	150x150x3	.8242
Proposed Approach using ResNet50	#174: @(conv5_block3_out)	150x150x3	.8309
Inception V3	#228: @(mixed7)	150x150x3	.8564
Proposed Approach using InceptionV3	#228: @(mixed7)	150x150x3	.8644

Table 3. Classification Accuracy of Various Approaches on *Cats and Dogs* Dataset
(**Second Classifier Used:** NN; **Metric Used:** Std. Deviation of Softmax scores,
Feature Map Size: 1x1024)

Approach	Secondary NN used on top of Layer	Image Size	Accuracy
ResNet50	#174: @(conv5_block3_out)	224x224x3	.9780
Proposed Approach using ResNet50	#174: @(conv5_block3_out)	224x224x3	.9860
Inception V3	#228: @(mixed7)	150x150x3	.9440
Proposed Approach using InceptionV3	#228: @(mixed7)	150x150x3	.9520

As is observed from Table 2, larger image sizes lead to higher accuracies. However,

the training times also increase.

Table 4. Classification Accuracy of Various Approaches on Caltech-101 Dataset
(**Second Classifier Used:** Binary-SVM Ensemble; **Metric Used:** Std. Deviation of SVM prediction scores, **Feature Map Size:** 1x4096)

Approach	Secondary SVM used on top of Layer	Image Size	Accuracy
AlexNet	-	227x227x3	.841
CNN-SVM Hybrid Approach [53]	#20: @(fc7)	227x227x3	.882
Proposed Approach using AlexNet	#20: @(fc7)	227x227x3	.898

As is observable from Table 2 to 4, the proposed approach outperforms other approaches on all the datasets used. It should be noted that dimensional reduction [54] is not used. Also, that the proposed approach is instance-based. Thus the processing time is more.

4. Conclusion and Future Work

In this paper, a straightforward and efficient learning system is investigated which combines deep learning with reinforcement learning. The proposed technique is simpler than other contemporary techniques found elsewhere. This is for the reason that others use high number of states while as ours uses only two states. Thus optimization is easy and the reward function is straightforward. Other approaches use visualization tasks like zoom and translation. We use a novel one i.e. rotation, being similar to tilt of visual field. Three databases have been used in the experimentation here. These are ImageNet, *Cats and Dogs* Dataset, and Caltech-101 Dataset. Benchmarking of the proposed classifier has been done. The proposed approach outperforms other approaches including ResNet50, InceptionV3, etc. on all the three datasets used. In future, more work would be done on making our approach faster by using techniques like dimensional reduction, or using smaller feature maps. Also, work would be done on using our approach on other interesting computer vision tasks like instance segmentation [55], etc.

Declarations

The authors declare no conflict of interest.

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