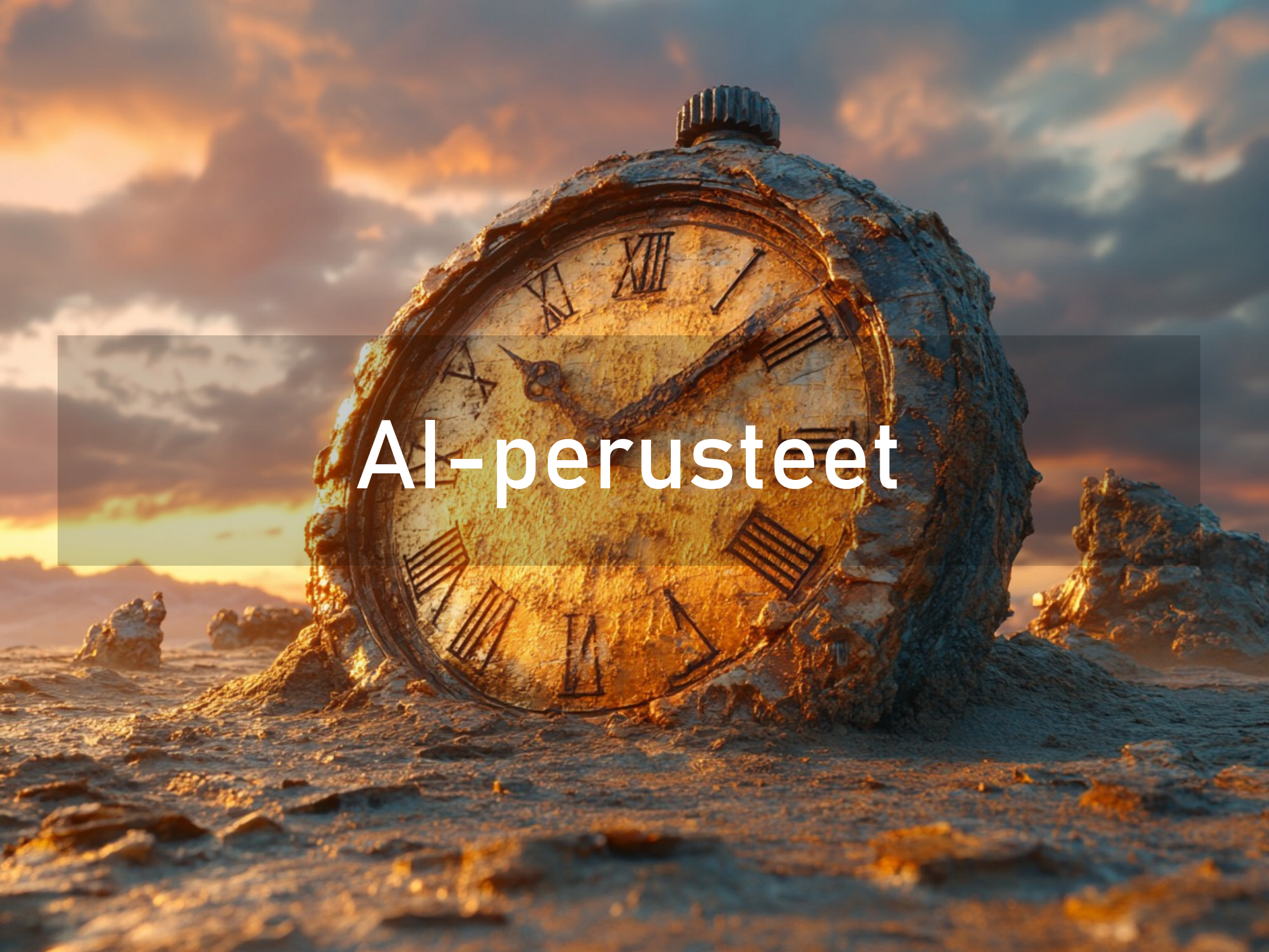
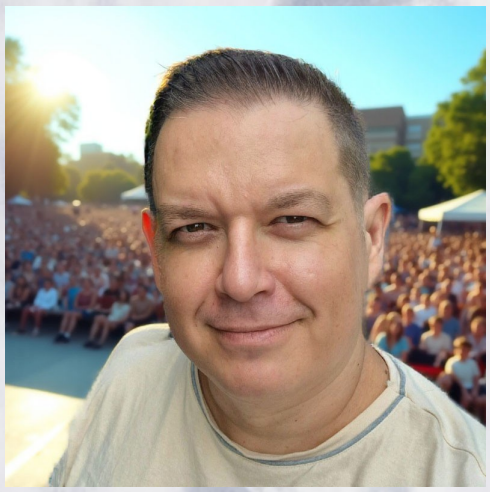

AI-perusteet

Oskari Uotinen

- Kouluttaja, konsultti 2008 ->
- InFlow 2010 ->
  - markkinointi, digitalisaatio
- InFlow Web Creations Oy 2017 ->
  - verkkosivusto- ja verkkokauppakehitys
- Tekoälyköt 2024 ->
  - Tekoälyn integroiminen osaksi yritysten liiketoimintaprosesseja











Sami Kallioniemi

- Fyysinen ikä 50v / henkinen ikä 23v
- Vaimo + poika
- Tampere
- Maatila Etelä-Thaimaassa
- Pyöräily, kuntosali, leffat, kalastus

- Aloittanut valokuvauksen 80-luvulla
- Digitaalista kuvankäsittelyä 90-luvulta
- Yrityskuvaukset still + video

- 2015 ensikosketus AI-maailmaan
- Visuaalinen markkinointi ja sisällöntuotanto
- Koulutus ja sparraus
- Brändityö ja tarinankerronta





Oppimistavoitteet

- **Perusymmärrys tekoälystä ja sen rajoitteista**
  – Osallistuja ymmärtää, mitä tekoäly on ja mitä se ei ole, sekä tunnistaa keskeiset huomioitavat asiat (esim. tietosuoja, tietoturva ja luotettavuus).
- **Tekoälyn käyttökohteiden tunnistaminen**
  – Osallistuja osaa tunnistaa oman työnsä ja organisaationsa kannalta keskeisiä tekoälyn sovelluskohteita.
- **Käytännön taitojen kehittäminen tekoälytyökaluissa**
  – Osallistuja osaa hyödyntää tekoälyä konkreettisesti mm. dokumenttien, tarjousten ja markkinointitekstien laadinnassa.

Miten olet käyttänyt tekoälyä?

Asiakas: "Pystyykö tälläisen tekemään?"

Sami: "Pystyy."



Vastakkainasettelu




AI

1950-1960 LISP/Prolog



1980-1990 Expert Systems



Machine Learning (koneoppiminen)



Machine Learning (koneoppiminen)



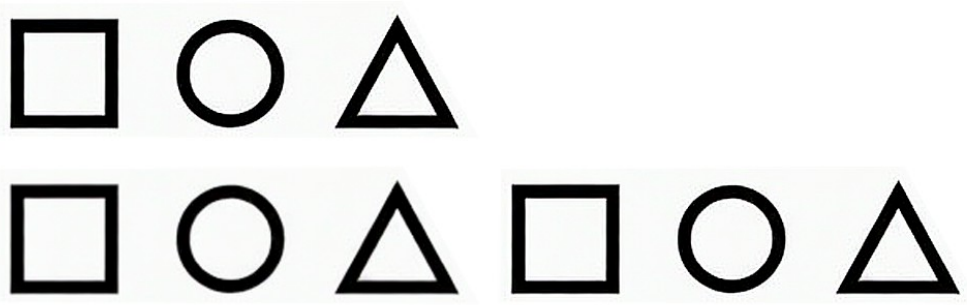


- 1952 Tammi-peli (Checkers)
- 1977 Ensimmäinen itseajava auto (Japanilainen Tsukuba lab)

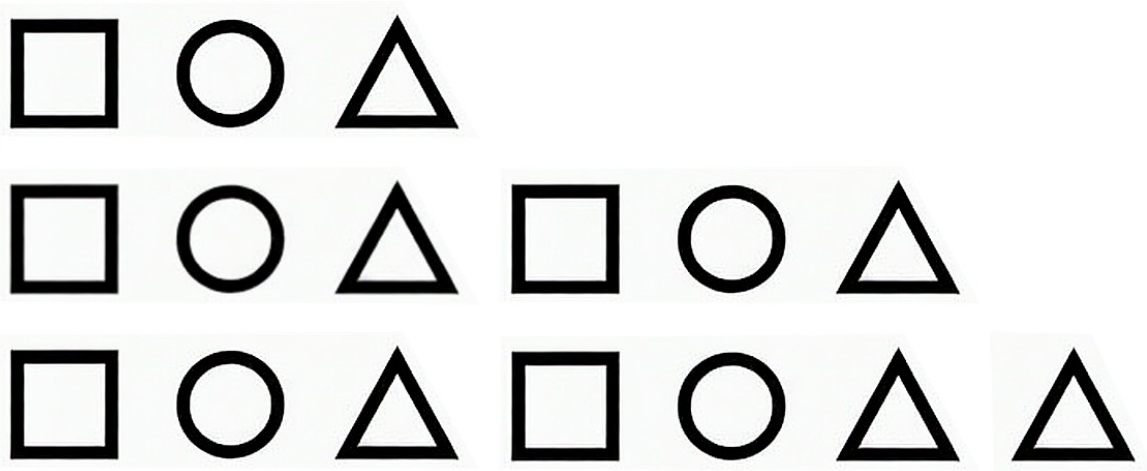
Machine Learning (koneoppiminen)
Hyvä etsimään kaavamaisuuksia



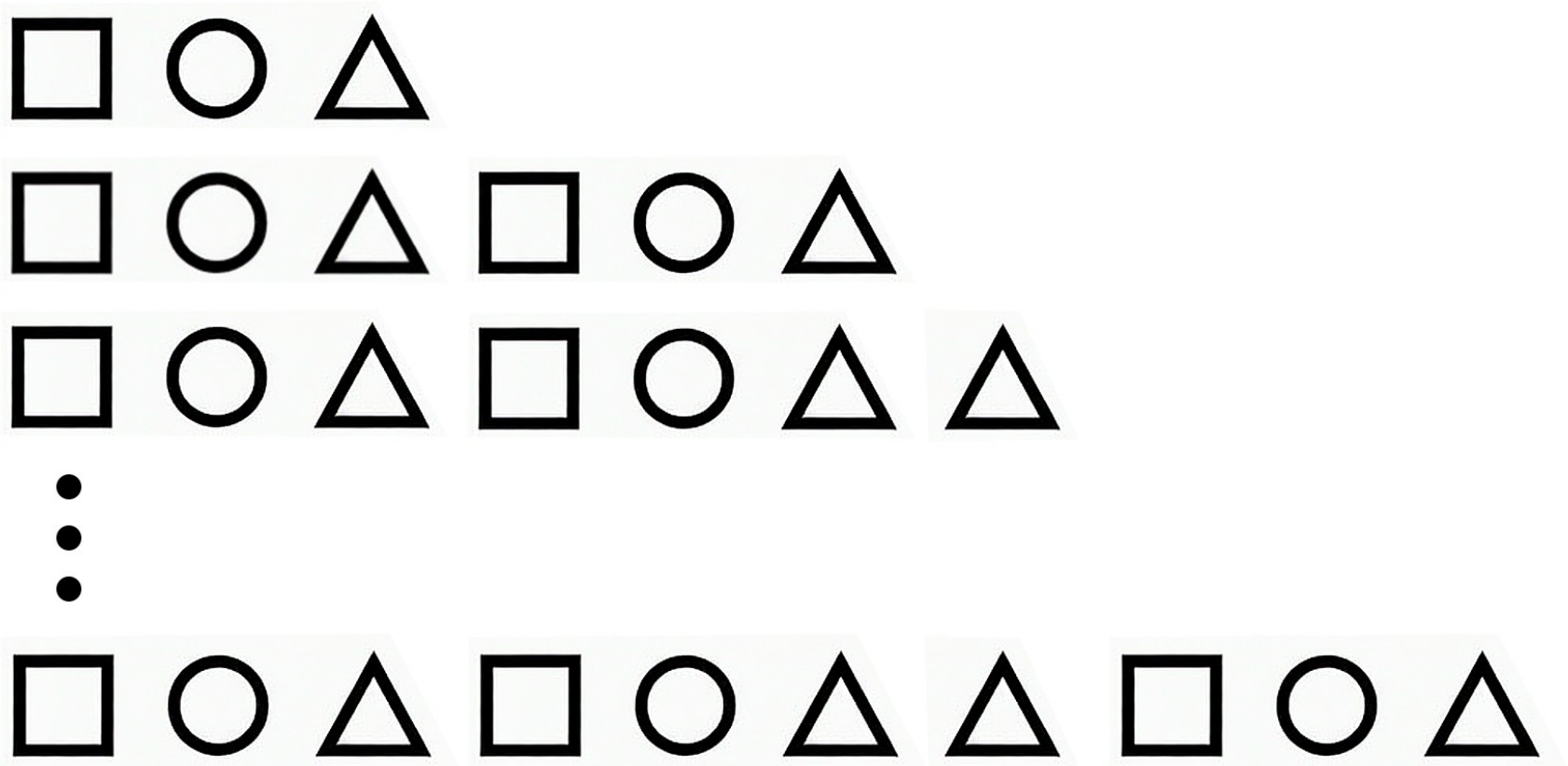
Machine Learning (koneoppiminen)



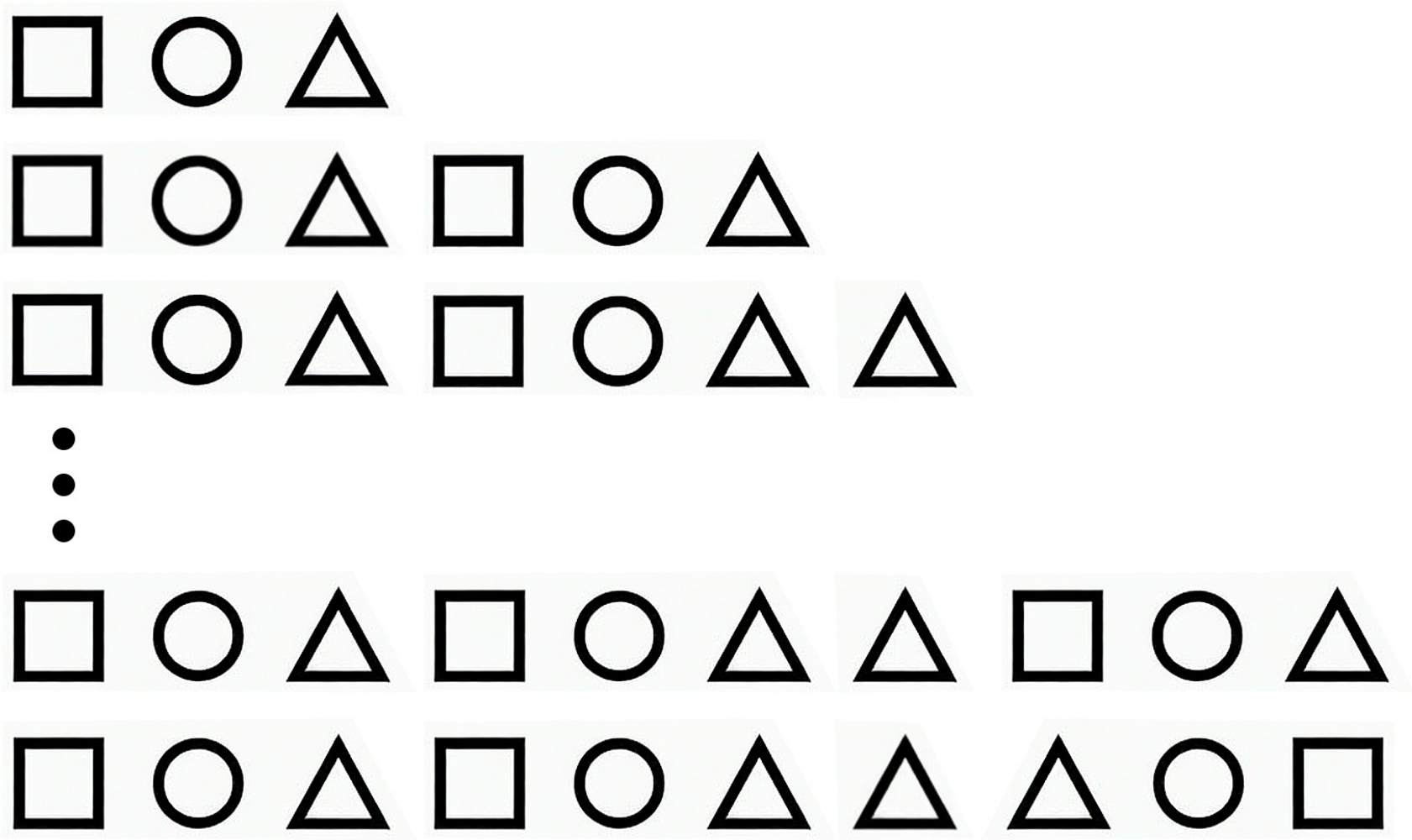
Machine Learning (koneoppiminen)



Machine Learning (koneoppiminen)



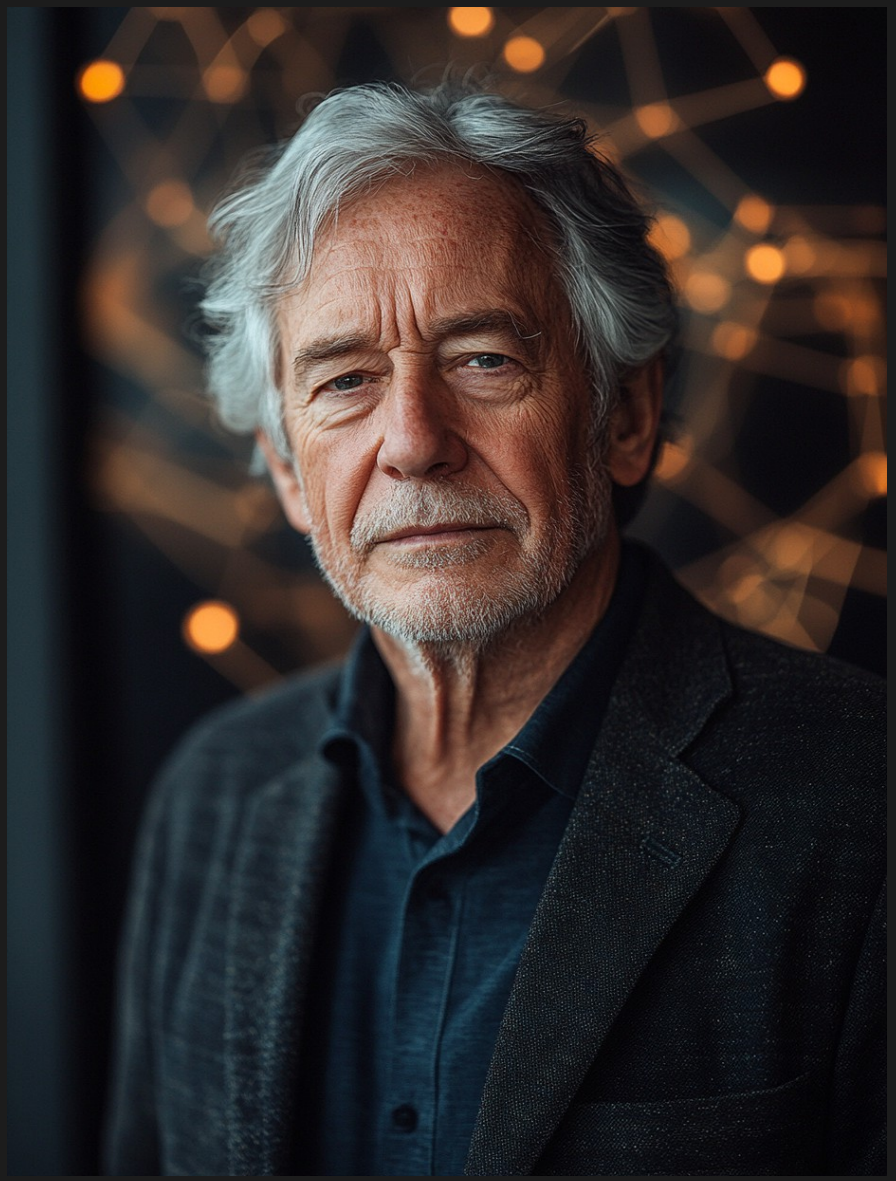
Machine Learning (koneoppiminen)



1996–1997 Garry Kasparov vs. IBM Deep Blue

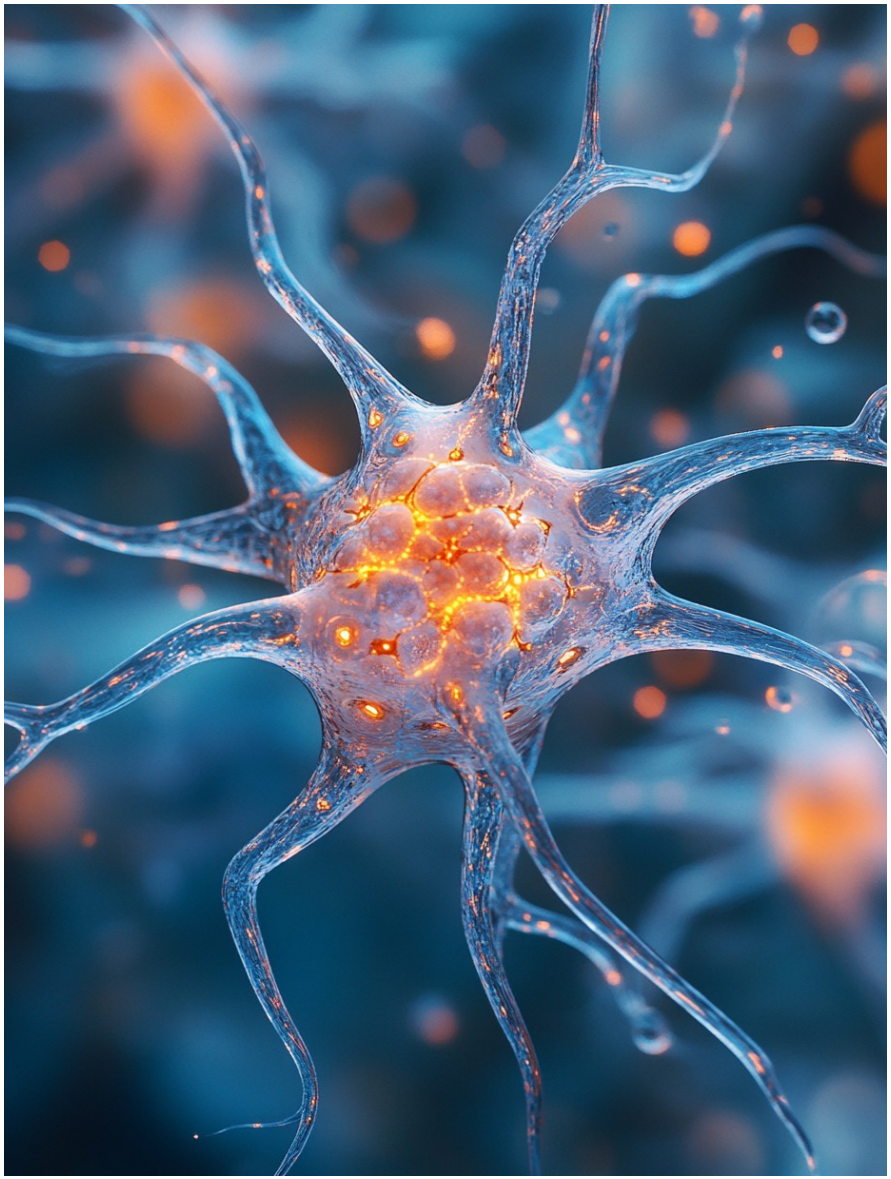


2006 Deep Learning (syväoppiminen)



- Geoffrey Hinton
- Syväoppimisen kummisetä
- Fysiikan Nobel 2024 (koneoppiminen neuroverkossa)
- DL tunnistaa kuvia, puhetta jne.

Neural Network (neuroverkko)

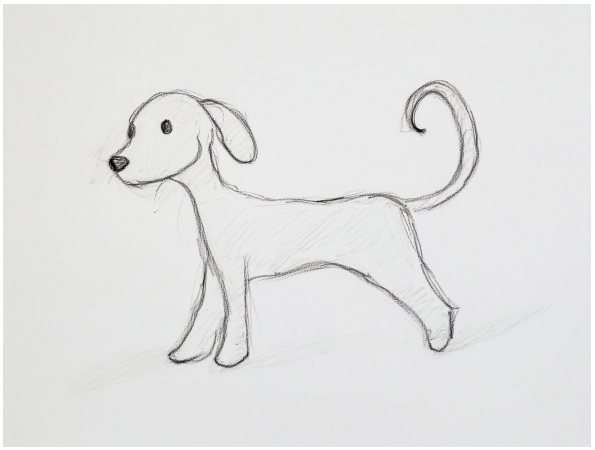


- Simuloi tapahtumia aivojen tapaan
- Ensimmäinen yhden tason neuroverkko 1957
- Aivojen tapaan arvaamattomia

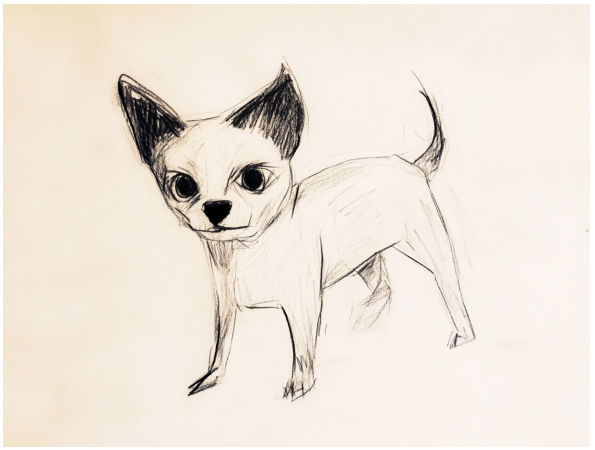
Whisper game (rikkinäinen puhelin)



"Piirrä koira"





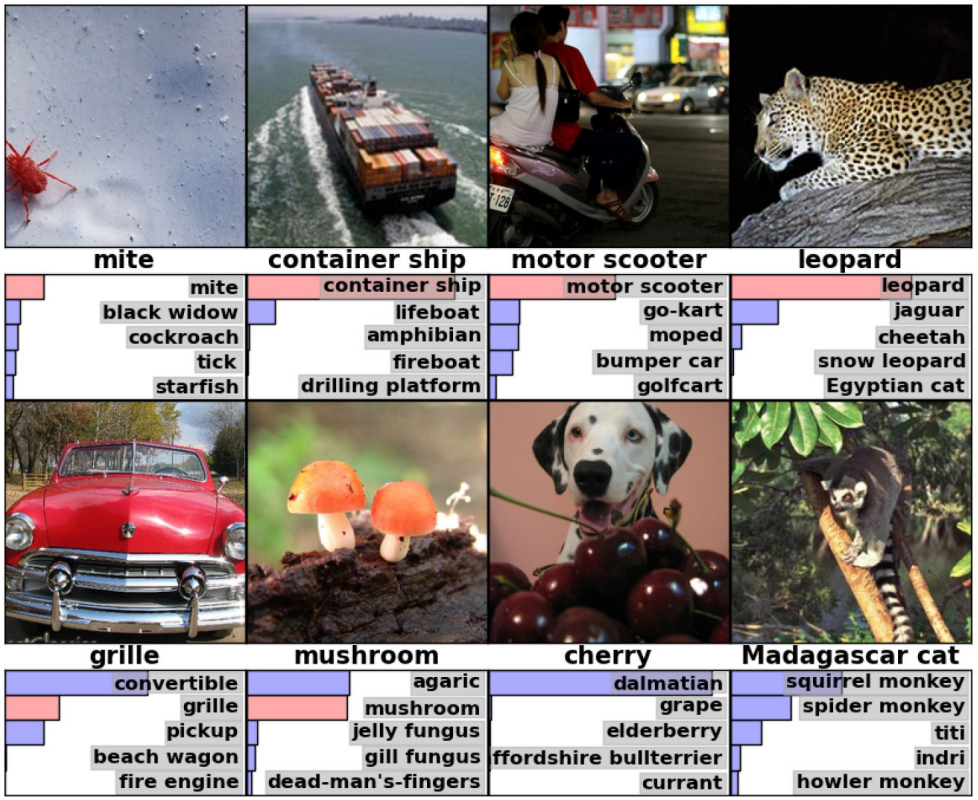








2012 AlexNet





- Nopeuttaa kuvakoulutusta ja vähentää ylioppimista
- Verkko saavutti 15,3% virhemarginaalin 2012 ImageNet kilpailussa

2012 AlexNet

ImageNet Classification with Deep Convolutional Neural Networks

Alex Krizhevsky
University of Toronto
kriz@cs.utoronto.ca

Ilya Sutskever
University of Toronto
ilya@cs.utoronto.ca

Geoffrey E. Hinton
University of Toronto
hinton@cs.utoronto.ca

Abstract

We trained a large, deep convolutional neural network to classify the 1.2 million high-resolution images in the ImageNet LSVRC-2010 contest into the 1000 different classes. On the test data, we achieved top-1 and top-5 error rates of 37.5% and 17.0% which is considerably better than the previous state-of-the-art. The neural network, which has 60 million parameters and 650,000 neurons, consists of five convolutional layers, some of which are followed by max-pooling layers, and three fully-connected layers with a final 1000-way softmax. To make training faster, we used non-saturating neurons and a very efficient GPU implementation of the convolution operation. To reduce overfitting in the fully-connected layers we employed a recently-developed regularization method called "dropout" that proved to be very effective. We also entered a variant of this model in the ILSVRC-2012 competition and achieved a winning top-5 test error rate of 15.3%, compared to 26.2% achieved by the second-best entry.

1 Introduction

Current approaches to object recognition make essential use of machine learning methods. To improve their performance, we can collect larger datasets, learn more powerful models, and use better techniques for preventing overfitting. Until recently, datasets of labeled images were relatively small — on the order of tens of thousands of images (e.g., NORB [16], Caltech-101/256 [8, 9], and CIFAR-10/100 [12]). Simple recognition tasks can be solved quite well with datasets of this size, especially if they are augmented with label-preserving transformations. For example, the current-best error rate on the MNIST digit-recognition task (<0.3%) approaches human performance [4]. But objects in realistic settings exhibit considerable variability, so to learn to recognize them it is necessary to use much larger training sets. And indeed, the shortcomings of small image datasets have been widely recognized (e.g., Pinto et al. [21]), but it has only recently become possible to collect labeled datasets with millions of images. The new larger datasets include LabelMe [23], which consists of hundreds of thousands of fully-segmented images, and ImageNet [6], which consists of over 15 million labeled high-resolution images in over 22,000 categories.

To learn about thousands of objects from millions of images, we need a model with a large learning capacity. However, the immense complexity of the object recognition task means that this problem cannot be specified even by a dataset as large as ImageNet, so our model should also have lots of prior knowledge to compensate for all the data we don't have. Convolutional neural networks (CNNs) constitute one such class of models [16, 11, 13, 18, 15, 22, 26]. Their capacity can be controlled by varying their depth and breadth, and they also make strong and mostly correct assumptions about the nature of images (namely, stationarity of statistics and locality of pixel dependencies). Thus, compared to standard feedforward neural networks with similarly-sized layers, CNNs have much fewer connections and parameters and so they are easier to train, while their theoretically-best performance is likely to be only slightly worse.

Despite the attractive qualities of CNNs, and despite the relative efficiency of their local architecture, they have still been prohibitively expensive to apply in large scale to high-resolution images. Luckily, current GPUs, paired with a highly-optimized implementation of 2D convolution, are powerful enough to facilitate the training of interestingly-large CNNs, and recent datasets such as ImageNet contain enough labeled examples to train such models without severe overfitting.

The specific contributions of this paper are as follows: we trained one of the largest convolutional neural networks to date on the subsets of ImageNet used in the ILSVRC-2010 and ILSVRC-2012 competitions [2] and achieved by far the best results ever reported on these datasets. We wrote a highly-optimized GPU implementation of 2D convolution and all the other operations inherent in training convolutional neural networks, which we make available publicly[1]. Our network contains a number of new and unusual features which improve its performance and reduce its training time, which are detailed in Section 3. The size of our network made overfitting a significant problem, even with 1.2 million labeled training examples, so we used several effective techniques for preventing overfitting, which are described in Section 4. Our final network contains five convolutional and three fully-connected layers, and this depth seems to be important: we found that removing any convolutional layer (each of which contains no more than 1% of the model's parameters) resulted in inferior performance.

In the end, the network's size is limited mainly by the amount of memory available on current GPUs and by the amount of training time that we are willing to tolerate. Our network takes between five and six days to train on two GTX 580 3GB GPUs. All of our experiments suggest that our results can be improved simply by waiting for faster GPUs and bigger datasets to become available.

2 The Dataset

ImageNet is a dataset of over 15 million labeled high-resolution images belonging to roughly 22,000 categories. The images were collected from the web and labeled by human labelers using Amazon's Mechanical Turk crowd-sourcing tool. Starting in 2010, as part of the Pascal Visual Object Challenge, an annual competition called the ImageNet Large-Scale Visual Recognition Challenge (ILSVRC) has been held. ILSVRC uses a subset of ImageNet with roughly 1000 images in each of 1000 categories. In all, there are roughly 1.2 million training images, 50,000 validation images, and 150,000 testing images.

ILSVRC-2010 is the only version of ILSVRC for which the test set labels are available, so this is the version on which we performed most of our experiments. Since we also entered our model in the ILSVRC-2012 competition, in Section 6 we report our results on this version of the dataset as well, for which test set labels are unavailable. On ImageNet, it is customary to report two error rates: top-1 and top-5, where the top-5 error rate is the fraction of test images for which the correct label is not among the five labels considered most probable by the model.

ImageNet consists of variable-resolution images, while our system requires a constant input dimensionality. Therefore, we down-sampled the images to a fixed resolution of 256×256. Given a rectangular image, we first rescaled the image such that the shorter side was of length 256, and then cropped out the central 256×256 patch from the resulting image. We did not pre-process the images in any other way, except for subtracting the mean activity over the training set from each pixel. So we trained our network on the (centered) raw RGB values of the pixels.

3 The Architecture

The architecture of our network is summarized in Figure 2. It contains eight learned layers — five convolutional and three fully-connected. Below, we describe some of the novel or unusual features of our network's architecture. Sections 3.1-3.4 are sorted according to our estimation of their importance, with the most important first.

[1] http://code.google.com/p/cuda-convnet/

3.1 ReLU Nonlinearity

The standard way to model a neuron's output f as a function of its input x is with $f(x) = \tanh(x)$ or $f(x) = (1 + e^{-x})^{-1}$. In terms of training time with gradient descent, these saturating nonlinearities are much slower than the non-saturating nonlinearity $f(x) = \max(0, x)$. Following Nair and Hinton [20], we refer to neurons with this nonlinearity as Rectified Linear Units (ReLUs). Deep convolutional neural networks with ReLUs train several times faster than their equivalents with tanh units. This is demonstrated in Figure 1, which shows the number of iterations required to reach 25% training error on the CIFAR-10 dataset for a particular four-layer convolutional network. This plot shows that we would not have been able to experiment with such large neural networks for this work if we had used traditional saturating neuron models.

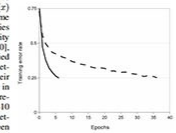


Figure 1: A four-layer convolutional neural network with ReLUs (**solid line**) reaches a 25% training error rate on CIFAR-10 six times faster than an equivalent network with tanh neurons (**dashed line**). The learning rates for each network were chosen independently to make training as fast as possible. No regularization of any kind was employed. The magnitude of the effect demonstrated here varies with network architecture, but networks with ReLUs consistently learn several times faster than equivalents with saturating neurons.

We are not the first to consider alternatives to traditional neuron models in CNNs. For example, Jarrett et al. [11] claim that the nonlinearity $f(x) = |\tanh(x)|$ works particularly well with their type of contrast normalization followed by local average pooling on the Caltech-101 dataset. However, on this dataset the primary concern is preventing overfitting, so the effect they are observing is different from the accelerated ability to fit the training set which we report when using ReLUs. Faster learning has a great influence on the performance of large models trained on large datasets.

3.2 Training on Multiple GPUs

A single GTX 580 GPU has only 3GB of memory, which limits the maximum size of the networks that can be trained on it. It turns out that 1.2 million training examples are enough to train networks which are too big to fit on one GPU. Therefore we spread the net across two GPUs. Current GPUs are particularly well-suited to cross-GPU parallelization, as they are able to read from and write to one another's memory directly, without going through host machine memory. The parallelization scheme that we employ essentially puts half of the kernels (or neurons) on each GPU, with one additional trick: the GPUs communicate only in certain layers. This means that, for example, the kernels of layer 3 take input from all kernel maps in layer 2. However, kernels in layer 4 take input only from those kernel maps in layer 3 which reside on the same GPU. Choosing the pattern of connectivity is a problem for cross-validation, but this allows us to precisely tune the amount of communication until it is an acceptable fraction of the amount of computation.

The resultant architecture is somewhat similar to that of the "columnar" CNN employed by Cireşan et al. [5], except that our columns are not independent (see Figure 2). This scheme reduces our top-1 and top-5 error rates by 1.7% and 1.2%, respectively, as compared with a net with half as many kernels in each convolutional layer trained on one GPU. The two-GPU net takes slightly less time to train than the one-GPU net[2].

[2] The one-GPU net actually has the same number of kernels as the two-GPU net in the final convolutional layer. This is because most of the net's parameters are in the first fully-connected layer, which takes the last convolutional layer as input. So to make the two nets have approximately the same number of parameters, we did not halve the size of the final convolutional layer (nor the fully-connected layers which follow). Therefore this comparison is biased in favor of the one-GPU net, since it is bigger than "half the size" of the two-GPU net.

3.3 Local Response Normalization

ReLUs have the desirable property that they do not require input normalization to prevent them from saturating. If at least some training examples produce a positive input to a ReLU, learning will happen in that neuron. However, we still find that the following local normalization scheme aids generalization. Denoting by $a^i_{x,y}$ the activity of a neuron computed by applying kernel i at position (x, y) and then applying the ReLU nonlinearity, the response-normalized activity $b^i_{x,y}$ is given by the expression

$$b^i_{x,y} = a^i_{x,y} / \left(k + \alpha \sum_{j=\max(0,i-n/2)}^{\min(N-1,i+n/2)} (a^j_{x,y})^2 \right)^{\beta}$$

where the sum runs over n "adjacent" kernel maps at the same spatial position, and N is the total number of kernels in the layer. The ordering of the kernel maps is of course arbitrary and determined before training begins. This sort of response normalization implements a form of lateral inhibition inspired by the type found in real neurons, creating competition for big activities amongst neuron outputs computed using different kernels. The constants k, n, α, and β are hyper-parameters whose values are determined using a validation set; we used $k = 2$, $n = 5$, $\alpha = 10^{-4}$, and $\beta = 0.75$. We applied this normalization after applying the ReLU nonlinearity in certain layers (see Section 3.5).

This scheme bears some resemblance to the local contrast normalization scheme of Jarrett et al. [11], but ours would be more correctly termed "brightness normalization", since we do not subtract the mean activity. Response normalization reduces our top-1 and top-5 error rates by 1.4% and 1.2%, respectively. We also verified the effectiveness of this scheme on the CIFAR-10 dataset: a four-layer CNN achieved a 13% test error rate without normalization and 11% with normalization[3].

3.4 Overlapping Pooling

Pooling layers in CNNs summarize the outputs of neighboring groups of neurons in the same kernel map. Traditionally, the neighborhoods summarized by adjacent pooling units do not overlap (e.g., [17, 11, 4]). To be more precise, a pooling layer can be thought of as consisting of a grid of pooling units spaced s pixels apart, each summarizing a neighborhood of size $z \times z$ centered at the location of the pooling unit. If we set $s = z$, we obtain traditional local pooling as commonly employed in CNNs. If we set $s < z$, we obtain overlapping pooling. This is what we use throughout our network, with $s = 2$ and $z = 3$. This scheme reduces the top-1 and top-5 error rates by 0.4% and 0.3%, respectively, as compared with the non-overlapping scheme $s = 2, z = 2$, which produces output of equivalent dimensions. We generally observe during training that models with overlapping pooling find it slightly more difficult to overfit.

3.5 Overall Architecture

Now we are ready to describe the overall architecture of our CNN. As depicted in Figure 2, the net contains eight layers with weights; the first five are convolutional and the remaining three are fully-connected. The output of the last fully-connected layer is fed to a 1000-way softmax which produces a distribution over the 1000 class labels. Our network maximizes the multinomial logistic regression objective, which is equivalent to maximizing the average across training cases of the log-probability of the correct label under the prediction distribution.

The kernels of the second, fourth, and fifth convolutional layers are connected only to those kernel maps in the previous layer which reside on the same GPU (see Figure 2). The kernels of the third convolutional layer are connected to all kernel maps in the second layer. The neurons in the fully-connected layers are connected to all neurons in the previous layer. Response-normalization layers follow the first and second convolutional layers. Max-pooling layers, of the kind described in Section 3.4, follow both response-normalization layers as well as the fifth convolutional layer. The ReLU non-linearity is applied to the output of every convolutional and fully-connected layer.

The first convolutional layer filters the $224 \times 224 \times 3$ input image with 96 kernels of size $11 \times 11 \times 3$ with a stride of 4 pixels (this is the distance between the receptive field centers of neighboring

[3] We cannot describe this network in detail due to space constraints, but it is specified precisely by the code and parameter files provided here: http://code.google.com/p/cuda-convnet/.

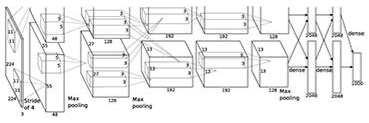


Figure 2: An illustration of the architecture of our CNN, explicitly showing the delineation of responsibilities between the two GPUs. One GPU runs the layer-parts at the top of the figure while the other runs the layer-parts at the bottom. The GPUs communicate only at certain layers. The network's input is 150,528-dimensional, and the number of neurons in the network's remaining layers is given by 253,440–186,624–64,896–64,896–43,264–4096–4096–1000.

neurons in a kernel map). The second convolutional layer takes as input the (response-normalized and pooled) output of the first convolutional layer and filters it with 256 kernels of size $5 \times 5 \times 48$. The third, fourth, and fifth convolutional layers are connected to one another without any intervening pooling or normalization layers. The third convolutional layer has 384 kernels of size $3 \times 3 \times 256$ connected to the (normalized, pooled) outputs of the second convolutional layer. The fourth convolutional layer has 384 kernels of size $3 \times 3 \times 192$, and the fifth convolutional layer has 256 kernels of size $3 \times 3 \times 192$. The fully-connected layers have 4096 neurons each.

4 Reducing Overfitting

Our neural network architecture has 60 million parameters. Although the 1000 classes of ILSVRC make each training example impose 10 bits of constraint on the mapping from image to label, this turns out to be insufficient to learn so many parameters without considerable overfitting. Below, we describe the two primary ways in which we combat overfitting.

4.1 Data Augmentation

The easiest and most common method to reduce overfitting on image data is to artificially enlarge the dataset using label-preserving transformations (e.g., [25, 4, 5]). We employ two distinct forms of data augmentation, both of which allow transformed images to be produced from the original images with very little computation, so the transformed images do not need to be stored on disk. In our implementation, the transformed images are generated in Python code on the CPU while the GPU is training on the previous batch of images. So these data augmentation schemes are, in effect, computationally free.

The first form of data augmentation consists of generating image translations and horizontal reflections. We do this by extracting random 224×224 patches (and their horizontal reflections) from the 256×256 images and training our network on these extracted patches[4]. This increases the size of our training set by a factor of 2048, though the resulting training examples are, of course, highly interdependent. Without this scheme, our network suffers from substantial overfitting, which would have forced us to use much smaller networks. At test time, the network makes a prediction by extracting five 224×224 patches (the four corner patches and the center patch) as well as their horizontal reflections (hence ten patches in all), and averaging the predictions made by the network's softmax layer on the ten patches.

The second form of data augmentation consists of altering the intensities of the RGB channels in training images. Specifically, we perform PCA on the set of RGB pixel values throughout the ImageNet training set. To each training image, we add multiples of the found principal components,

[4] This is the reason why the input images in Figure 2 are $224 \times 224 \times 3$-dimensional.

with magnitudes proportional to the corresponding eigenvalues times a random variable drawn from a Gaussian with mean zero and standard deviation 0.1. Therefore to each RGB image pixel $I_{xy} = [I^R_{xy}, I^G_{xy}, I^B_{xy}]^T$ we add the following quantity:

$$[p_1, p_2, p_3][\alpha_1\lambda_1, \alpha_2\lambda_2, \alpha_3\lambda_3]^T$$

where p_i and λ_i are ith eigenvector and eigenvalue of the 3×3 covariance matrix of RGB pixel values, respectively, and α_i is the aforementioned random variable. Each α_i is drawn only once for all the pixels of a particular training image until that image is used for training again, at which point it is re-drawn. This scheme approximately captures an important property of natural images, namely, that object identity is invariant to changes in the intensity and color of the illumination. This scheme reduces the top-1 error rate by over 1%.

4.2 Dropout

Combining the predictions of many different models is a very successful way to reduce test errors [1, 3], but it appears to be too expensive for big neural networks that already take several days to train. There is, however, a very efficient version of model combination that only costs about a factor of two during training. The recently-introduced technique, called "dropout" [10], consists of setting to zero the output of each hidden neuron with probability 0.5. The neurons which are "dropped out" in this way do not contribute to the forward pass and do not participate in back-propagation. So every time an input is presented, the neural network samples a different architecture, but all these architectures share weights. This technique reduces complex co-adaptations of neurons, since a neuron cannot rely on the presence of particular other neurons. It is, therefore, forced to learn more robust features that are useful in conjunction with many different random subsets of the other neurons. At test time, we use all the neurons but multiply their outputs by 0.5, which is a reasonable approximation to taking the geometric mean of the predictive distributions produced by the exponentially-many dropout networks.

We use dropout in the first two fully-connected layers of Figure 2. Without dropout, our network exhibits substantial overfitting. Dropout roughly doubles the number of iterations required to converge.

5 Details of learning

We trained our models using stochastic gradient descent with a batch size of 128 examples, momentum of 0.9, and weight decay of 0.0005. We found that this small amount of weight decay was important for the model to learn. In other words, weight decay here is not merely a regularizer: it reduces the model's training error. The update rule for weight w was

$$v_{i+1} := 0.9 \cdot v_i - 0.0005 \cdot \epsilon \cdot w_i - \epsilon \cdot \left\langle \frac{\partial L}{\partial w} \Big|_{w_i} \right\rangle_{D_i}$$

$$w_{i+1} := w_i + v_{i+1}$$

where i is the iteration index, v is the momentum variable, ϵ is the learning rate, and $\left\langle \frac{\partial L}{\partial w} \Big|_{w_i} \right\rangle_{D_i}$ is the average over the ith batch D_i of the derivative of the objective with respect to w, evaluated at w_i.

We initialized the weights in each layer from a zero-mean Gaussian distribution with standard deviation 0.01. We initialized the neuron biases in the second, fourth, and fifth convolutional layers, as well as in the fully-connected hidden layers, with the constant 1. This initialization accelerates the early stages of learning by providing the ReLUs with positive inputs. We initialized the neuron biases in the remaining layers with the constant 0.

We used an equal learning rate for all layers, which we adjusted manually throughout training. The heuristic which we followed was to divide the learning rate by 10 when the validation error rate stopped improving with the current learning rate. The learning rate was initialized at 0.01 and

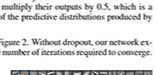


Figure 3: 96 convolutional kernels of size $11 \times 11 \times 3$ learned by the first convolutional layer on the $224 \times 224 \times 3$ input images. The top 48 kernels were learned on GPU 1 while the bottom 48 kernels were learned on GPU 2. See Section 6.1 for details.

reduced three times prior to termination. We trained the network for roughly 90 cycles through the training set of 1.2 million images, which took five to six days on two NVIDIA GTX 580 3GB GPUs.

6 Results

Our results on ILSVRC-2010 are summarized in Table 1. Our network achieves top-1 and top-5 test set error rates of **37.5%** and **17.0%**[5]. The best performance achieved during the ILSVRC-2010 competition was 47.1% and 28.2% with an approach that averages the predictions produced from six sparse-coding models trained on different features [2], and since then the best published results are 45.7% and 25.7% with an approach that averages the predictions of two classifiers trained on Fisher Vectors (FVs) computed from two types of densely-sampled features [24].

Model	Top-1	Top-5
Sparse coding [2]	*47.1%*	*28.2%*
SIFT + FVs [24]	*45.7%*	*25.7%*
CNN	**37.5%**	**17.0%**

Table 1: Comparison of results on ILSVRC-2010 test set. In *italics* are best results achieved by others.

We also entered our model in the ILSVRC-2012 competition and report our results in Table 2. Since the ILSVRC-2012 test set labels are not publicly available, we cannot report test error rates for all the models that we tried. In the remainder of this paragraph, we use validation and test error rates interchangeably because in our experience they do not differ by more than 0.1% (see Table 2). The CNN described in this paper achieves a top-5 error rate of 18.2%. Averaging the predictions of five similar CNNs gives an error rate of 16.4%. Training one CNN, with an extra sixth convolutional layer over the last pooling layer, to classify the entire ImageNet Fall 2011 release (15M images, 22K categories), and then "fine-tuning" it on ILSVRC-2012 gives an error rate of 16.6%. Averaging the predictions of two CNNs that were pre-trained on the entire Fall 2011 release with the aforementioned five CNNs gives an error rate of **15.3%**. The second-best contest entry achieved an error rate of 26.2% with an approach that averages the predictions of several classifiers trained on FVs computed from different types of densely-sampled features [7].

Finally, we also report our error rates on the Fall 2009 version of ImageNet with 10,184 categories and 8.9 million images. On this dataset we follow the convention in the literature of using half of the images for training and half for testing. Since there is no established test set, our split necessarily differs from the splits used by previous authors, but this does not affect the results appreciably. Our top-1 and top-5 error rates on this dataset are **67.4%** and **40.9%**, attained by the net described above but with an additional, sixth convolutional layer over the last pooling layer. The best published results on this dataset are 78.1% and 60.9% [19].

Model	Top-1 (val)	Top-5 (val)	Top-5 (test)
SIFT + FVs [7]			26.2%
1 CNN	40.7%	18.2%	—
5 CNNs	38.1%	16.4%	**16.4%**
1 CNN*	39.0%	16.6%	—
7 CNNs*	36.7%	15.4%	**15.3%**

Table 2: Comparison of error rates on ILSVRC-2012 validation and test sets. In *italics* are best results achieved by others. Models with an asterisk* were "pre-trained" to classify the entire ImageNet 2011 Fall release. See Section 6 for details.

6.1 Qualitative Evaluations

Figure 3 shows the convolutional kernels learned by the network's two data-connected layers. The network has learned a variety of frequency- and orientation-selective kernels, as well as various colored blobs. Notice the specialization exhibited by the two GPUs, a result of the restricted connectivity described in Section 3.5. The kernels on GPU 1 are largely color-agnostic, while the kernels on on GPU 2 are largely color-specific. This kind of specialization occurs during every run and is independent of any particular random weight initialization (modulo a renumbering of the GPUs).

[5] The error rates without averaging predictions over ten patches as described in Section 4.1 are 39.0% and 18.3%.



Figure 4: (**Left**) Eight ILSVRC-2010 test images and the five labels considered most probable by our model. The correct label is written under each image, and the probability assigned to the correct label is also shown with a red bar (if it happens to be in the top 5). (**Right**) Five ILSVRC-2010 test images in the first column. The remaining columns show the six training images that produce feature vectors in the last hidden layer with the smallest Euclidean distance from the feature vector for the test image.

In the left panel of Figure 4 we qualitatively assess what the network has learned by computing its top-5 predictions on eight test images. Notice that even off-center objects, such as the mite in the top-left, can be recognized by the net. Most of the top-5 labels appear reasonable. For example, only other types of cat are considered plausible labels for the leopard. In some cases (grille, cherry) there is genuine ambiguity about the intended focus of the photograph.

Another way to probe the network's visual knowledge is to consider the feature activations induced by an image at the last, 4096-dimensional hidden layer. If two images produce feature activation vectors with a small Euclidean separation, we can say that the higher levels of the neural network consider them to be similar. Figure 4 shows five images from the test set and the six images from the training set that are most similar to each of them according to this measure. Notice that at the pixel level, the retrieved training images are generally not close in L2 to the query images in the first column. For example, the retrieved dogs and elephants appear in a variety of poses. We present the results for many more test images in the supplementary material.

Computing similarity by using Euclidean distance between two 4096-dimensional, real-valued vectors is inefficient, but it could be made efficient by training an auto-encoder to compress these vectors to short binary codes. This should produce a much better image retrieval method than applying auto-encoders to the raw pixels [14], which does not make use of image labels and hence has a tendency to retrieve images with similar patterns of edges, whether or not they are semantically similar.

7 Discussion

Our results show that a large, deep convolutional neural network is capable of achieving record-breaking results on a highly challenging dataset using purely supervised learning. It is notable that our network's performance degrades if a single convolutional layer is removed. For example, removing any of the middle layers results in a loss of about 2% for the top-1 performance of the network. So the depth really is important for achieving our results.

To simplify our experiments, we did not use any unsupervised pre-training even though we expect that it will help, especially if we obtain enough computational power to significantly increase the size of the network without obtaining a corresponding increase in the amount of labeled data. Thus far, our results have improved as we have made our network larger and trained it longer but we still have many orders of magnitude to go in order to match the infero-temporal pathway of the human visual system. Ultimately we would like to use very large and deep convolutional nets on video sequences where the temporal structure provides very helpful information that is missing or far less obvious in static images.

2015 Google DeepDream



Wikipedia

DeepDream - Wiki…



TensorFlow

DeepDream | TensorFlow Core



YouTube

Google's DeepDream: A New Dig…



The Guardian

Deep Dream become an art m…



YouTube

Vincent Van Gogh in Google DeepDre…



Gallereo

Artist Spotlight: Google Deep Dream

2020-luku Foundation Model (perustamalli)

- **Large Language Model LLM**

→ Otetaan kieli jota mallinnetaan

→ Tehdään ennustuksia/arvauksia sen perusteella, kun nähdään jotain sanoja. Sen jälkeen ennustetaan mitä sanoja tulee seuraavaksi.

- Kevyt versio kännyköiden Auto Complete
- ChatGPT käyttää LLM:ää (ChatBot)

Prompt: "Mistä tulee lyhenne chatgpt?"

- "Mistä tulee lyhenne chatgpt? Chat" ...
- "Mistä tulee lyhenne chatgpt? Chat Generative" ...
- "Mistä tulee lyhenne chatgpt? Chat Generative Pre-trained" ...
- **"Chat Generative Pre-trained Transformer"**

2020-luku Foundation Model (perustamalli)

- **Äänimalli**
- **Kuva- ja videomalli**
    - Näistä voidaan tehdä Deep Fake (syväväärennös)
    - https://www.youtube.com/watch?v=3hRtxGBgsMw

    - Jos Deepfake-video sisältää valheellista tai loukkaavaa sisältöä esim. ystävästäsi ja se leviää muiden nähtäväksi, se saattaa täyttää kunnianloukkauksen tunnusmerkistön.

GenAI (Generatiivinen tekoäly)

- Generatiivinen tekoäly on tekoälyn osa-alue, joka luo uutta sisältöä, kuten kuvia, tekstiä, ääntä ja videoita
- Esim. Midjourney, Stable Diffusion tai DALL-E, on suunniteltu tuottamaan realistisia ja monimutkaisia kuvia
- Ne eivät optimoi yksinkertaisia geometrisiä muotoja, vaan pyrkivät jäljittelemään luonnollisia ja epätäydellisiä piirteitä, joita löytyy oikeista kuvista

Prompt (kehote)

- Prompt (kehote): lause kuvailee mitä haluat tehdä
- Promptaaminen (prompt engineering)
- Sanajärjestyksellä on merkitystä
- Positiivinen ja negatiivinen prompti

- **Positivinen prompti:**

  Erittäin realistinen näkymä rauhallisesta kaupungista päiväsaikaan. Puhdasta mukulakivikatua reunustavat viehättävät talot ja pienet paikalliset kaupat. Ihmiset kävelevät, pyöräilevät ja nauttivat raikkaasta ilmasta. Kauniita puita, joissa on vehreät, rehevät lehdet, on ripoteltu ympäri kaupunkia, mikä lisää maiseman kauneutta. Lämmin auringonvalo valaisee pehmeästi rakennuksia ja katuja, luoden kutsuvan ja elävän ilmapiirin. Kattojen päällä ja taivaalla lentää lintuja, jotka tuovat eloa näkymään. Kuvankauniilla kaupunginaukiolla on penkkejä, kukkia ja vanha kivinen suihkulähde, joka toimii keskeisenä maamerkkinä. Taivas on kirkkaan sininen, ja siellä leijuu pehmeitä valkoisia pilviä, jotka herättävät rauhan ja levollisuuden tunteen. Elävät, kirkkaat ja yksityiskohtaiset tekstuurit luovat elävän, ystävällisen kaupunkiympäristön, jossa on elokuvamainen ja dramaattinen valaistus. Korkearesoluutioinen ja yksityiskohtainen kuva tuo kaupungin elävästi esiin.

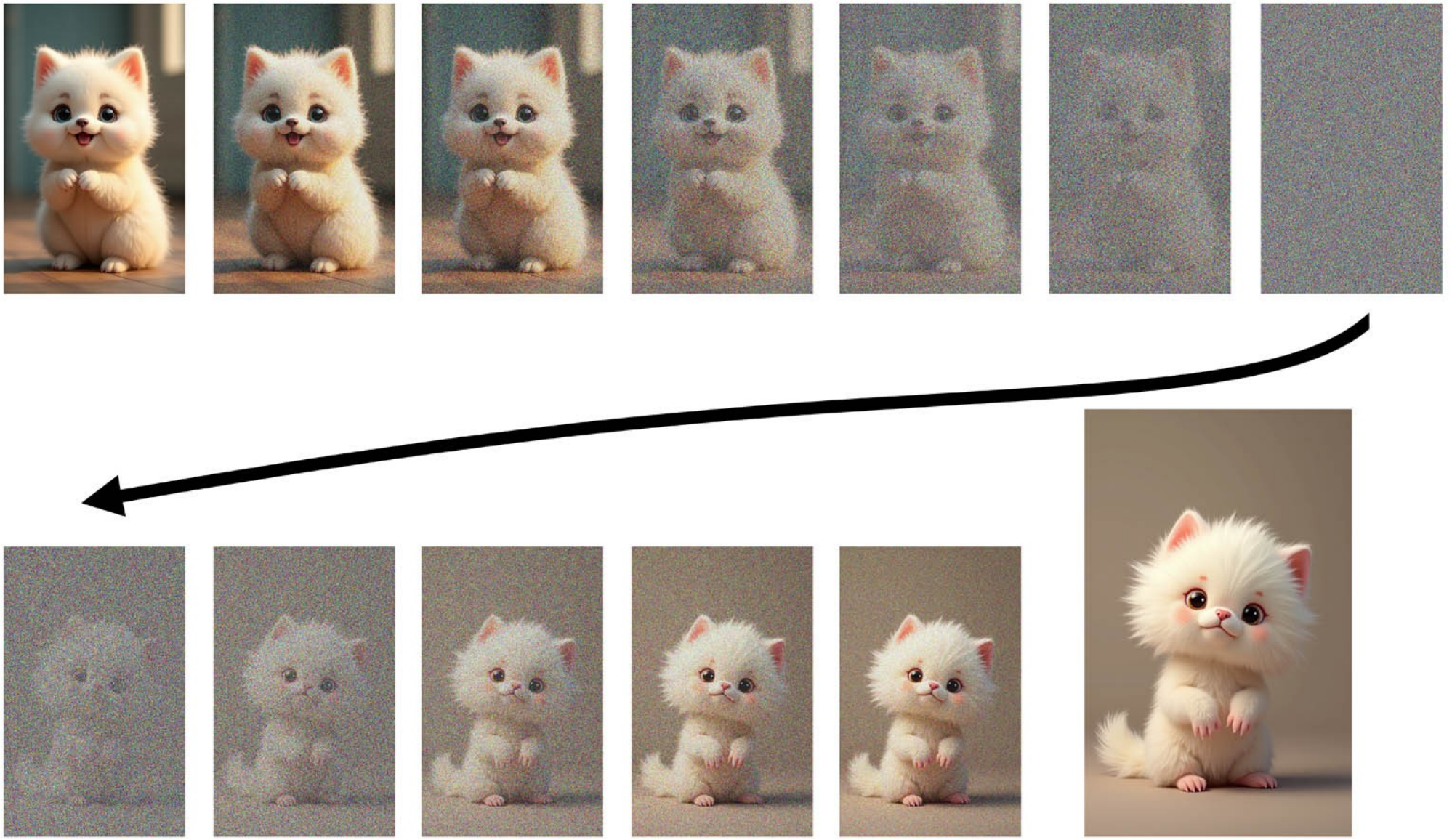
- **Negatiivinen prompti:**

  Modernit pilvenpiirtäjät, autot, epätarkka





Kuinka kuvan luonti toimii (diffusion model)



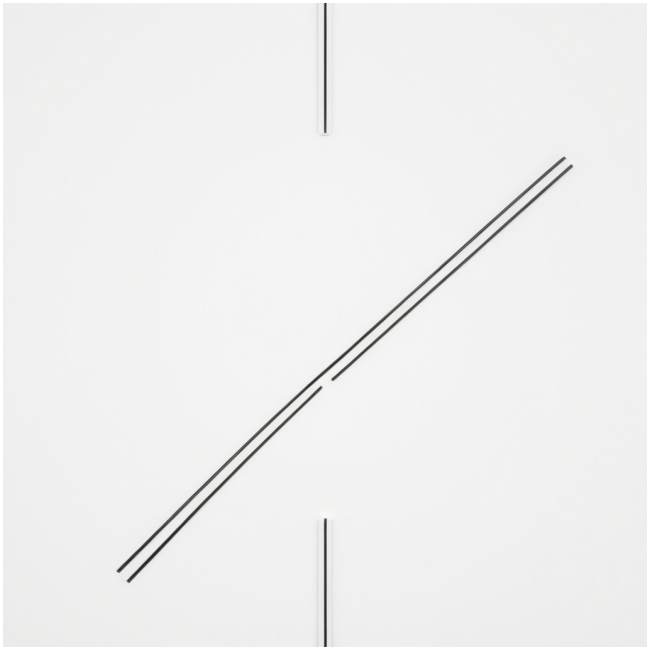
- Prompt: a very cute fluffy creature

Rajoitteet Generatiivisessa tekoälyssä



Geometriset muodot ja symmetria







- Prompt: single straight line

Rajoitteet Generatiivisessa tekoälyssä



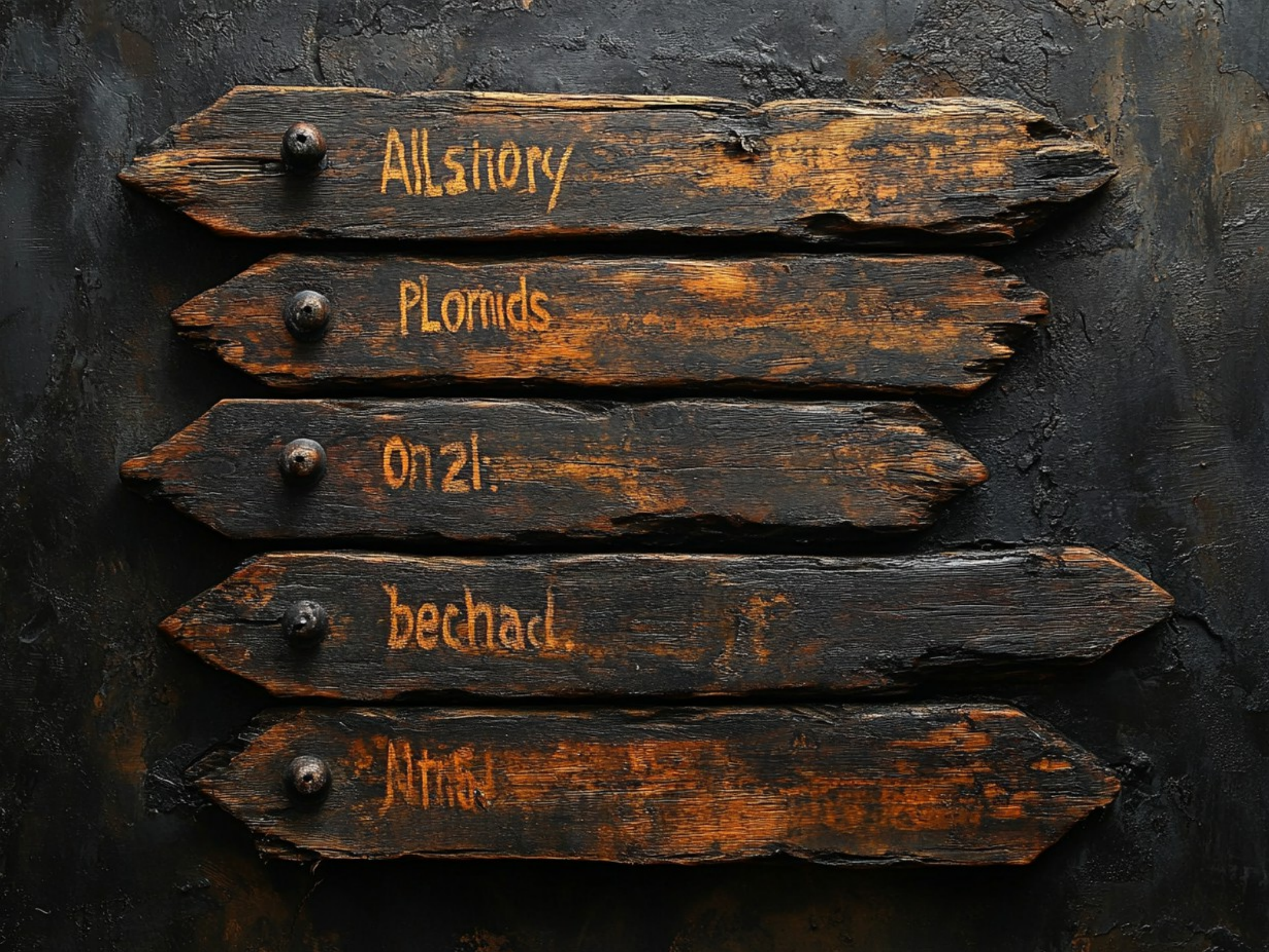












Allstory
Plomids
on 21:
bechad.


Kallaniemi


KALLIONIEMI

Sensuuri



Prompt: A close-up of a human hand showing the middle finger, isolated against a solid black background...

Sensuuri



Prompt: ...The middle finger nail is prominently visible with a hyper-realistic level of detail, showing natural imperfections, slight ridges, and realistic reflection from the lighting. The entire hand is visible in a natural, lifelike pose, with the fingers positioned to frame the middle finger as the central focus


Suurin rajoite olet SINÄ

Sontaa sisään = Sontaa ulos



...vaikka kinuskilla kuorruttaisi

Pyörää ei tarvitse keksiä uudelleen



Prompt: A modern office setting with a team of stressed designers and developers sitting around a conference table. On a large presentation screen, a simple image of a classic wheel is displayed as if it were part of a corporate pitch. One person stands in front of the screen, confidently presenting 'New Wheel Concept' with a serious expression, while the others sit with confused or bored faces. Coffee cups, laptops, and sticky notes are scattered on the table. The atmosphere is humorous and ironic, highlighting the absurdity of reinventing something so simple. The lighting is bright, office-like, with soft cinematic color grading

Midjourney 2022







Stable Diffusion 2022



Prompti: mudmonsters in mudpool, daylight, realistic

Stable Diffusion 2022



Prompti: old man sitting in a bar

Stable Diffusion 2023



Stable Diffusion 2025



Stable Diffusion 2025



Kaava / Formula

Kohde + ympäristö + keskeiset elementit + kamera + efektit



Prompti: 50 vuotias harmaa hiuksinen mies kävelee metsäpolkua pitkin. Metsässä on kuusimetsää. Metsässä kajastaa laskeva aurinko puiden takaa. Puun oksalla pöllö. Laajakulmakamera 20mm linssillä. Elokuvamainen sävytys. Ultra-realistinen

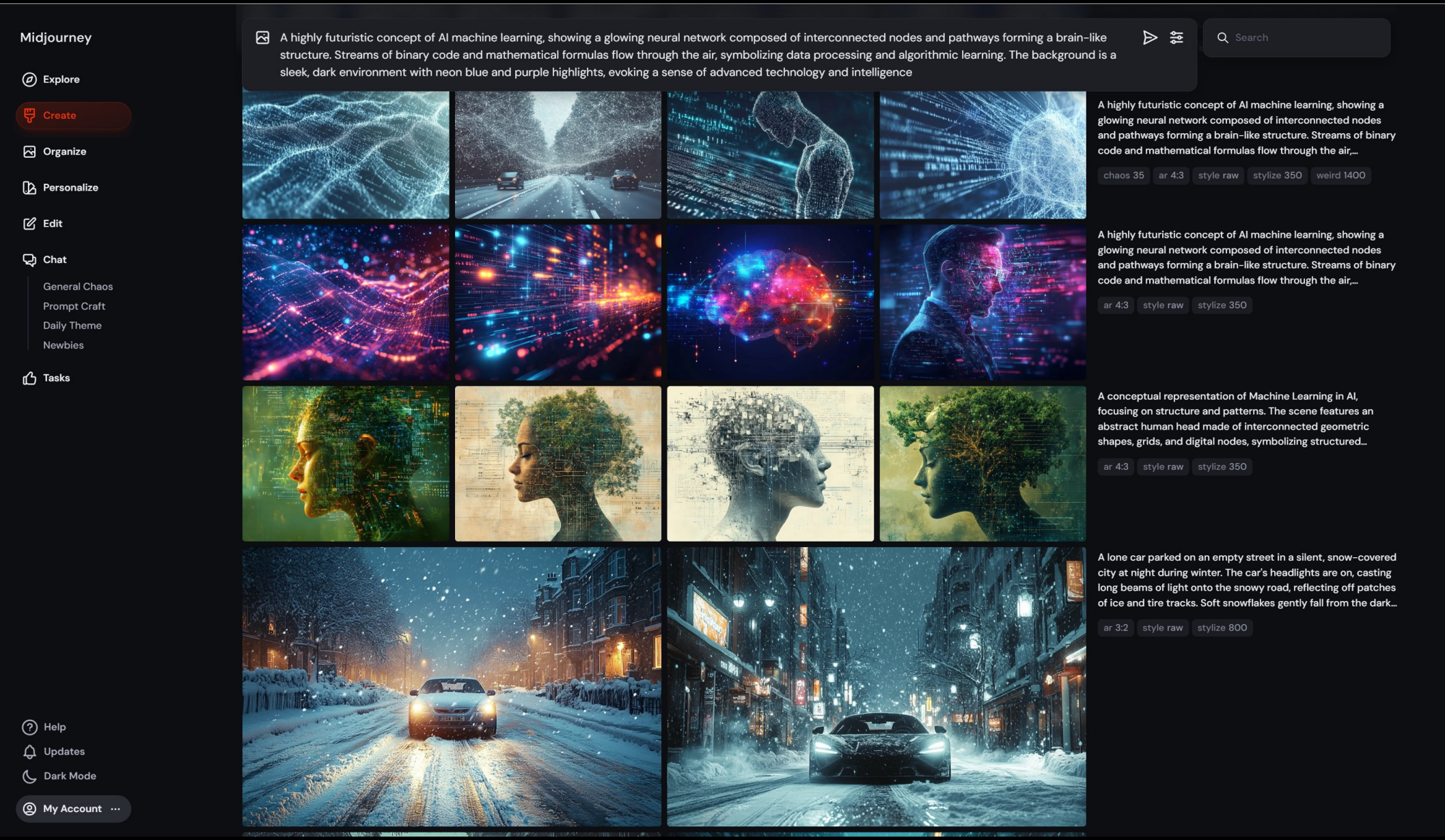
Kaava / Formula

"Lisää kuvaan lampi"

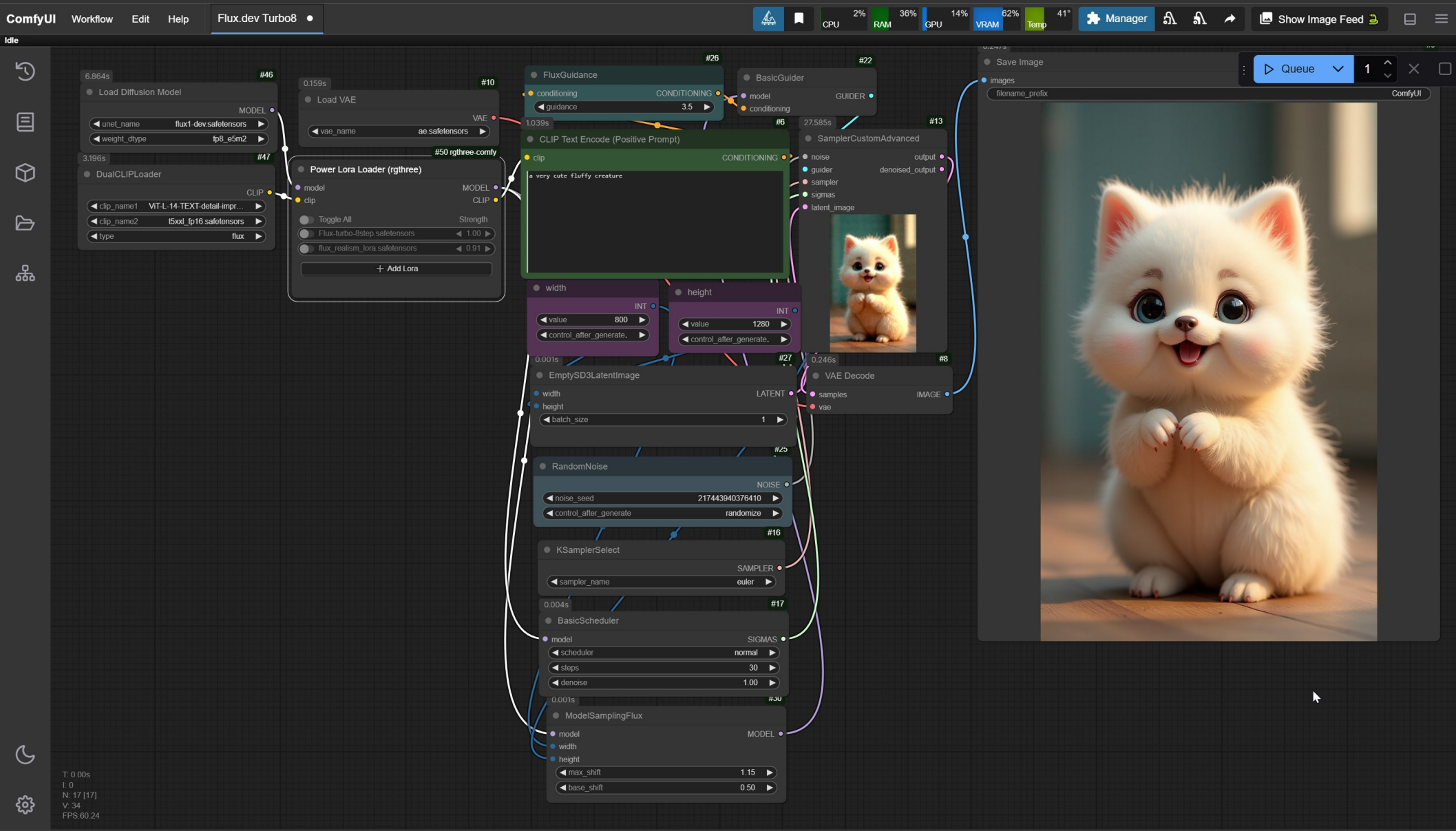


"Ultra-realistic cinematic scene of a 50-year-old gray-haired man walking along a narrow forest trail surrounded by dense spruce trees. A tranquil pond reflects the surrounding trees and the soft glow of the setting sun, adding a serene, mirror-like effect to the scene. The warm golden rays of the sun filter through the tree trunks, casting long shadows across the path and the water's surface. A majestic owl sits perched on a tree branch, watching quietly from above. Captured with a wide-angle 20mm lens, creating a sense of depth and scale. The atmosphere is calm, peaceful, and immersive, with cinematic color grading that emphasizes the natural beauty of the forest. The man appears thoughtful and introspective as he walks along the trail, **with the pond adding an element of stillness and reflection**."

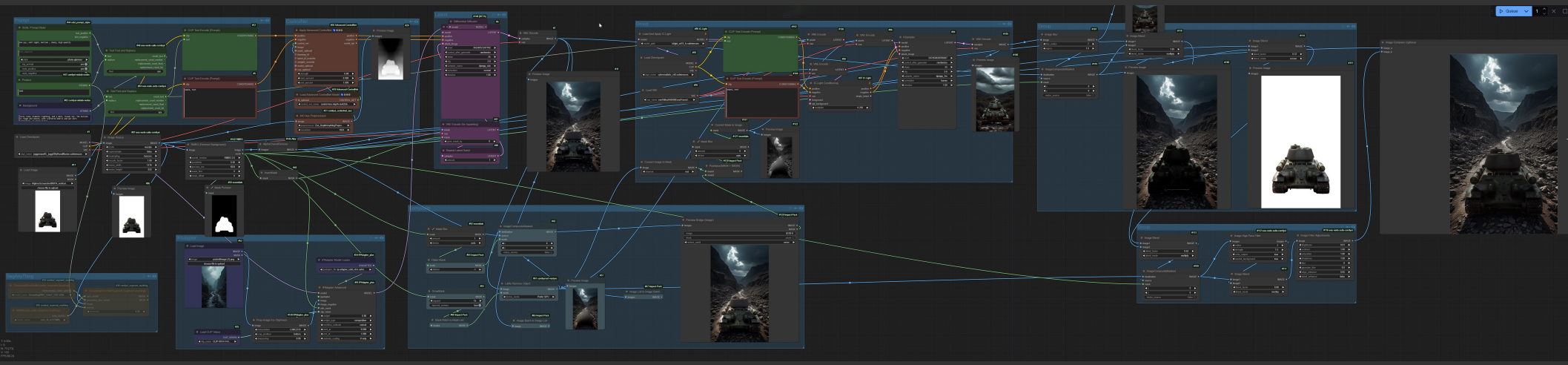
Midjourney käyttöliittymä



Stable Diffusion (ComfyUI)



Stable Diffusion (ComfyUI)





3D-malli


File
Edit
Window
Tools
Build
Select
Actor
Help
t34_tes3
Selection Mode
Platforms
Perspective
Lit
Show
Content Drawer
Output Log
Cmd
Enter Console Command


57


57



Yrityskuvaus (kuvituskuvat)





Yrityskuvaus (kuvituskuvat)





Yrityskuvaus (kuvituskuvat)







Yrityskuvaus (tuotekuvat)





Tärkeitä kontrolleja (GenAI)

Kategoria	Esimerkki
Kategoria	Esimerkki
Ikä	Lapsi, Teini, Aikuinen, Vanhus
Valaistus	Pehmeä valo, Kohdevalo, Takavalaistus
Vuorokaudenaika	Aamunkoitto, Auringonlasku, Yö
Ympäristö	Metsä, Kaupunki, Avaruus, Abstrakti
Perspektiivi	Matalakulma, Hartiakulma, Ylhäältä
Tyyli	Realistinen, Piirros, Cyberpunk
Tunnelma	Rauhallinen, Dramaattinen, Mystinen
Väripaletti	Mustavalkoinen, Pastelli, Neon
Vartalotyyppi	Pitkä, Lyhyt, Lihaksikas, Hoikka
Kasvonpiirteet	Terävä leuka, Suuret silmät, Pisamat
Rekvisiitta	Miekka, Kannettava tietokone, Lentävä auto
Symbolit	Kello, Elämän puu, Tiimalasi
Asento	Istuva, Hyppäävä, Juokseva
Ilme	Hymyilevä, Vihainen, Yllättynyt
Eläimet	Kissa, Koira, Lintu, Fantasiakäärme
Kameran linssi	50mm linssi, Laajakulma, Makrokuva
Taustan väri	Musta, Valkoinen, Sumuinen
Objektien koko	Pieni, Keskikokoinen, Suuri
Rakennukset	Keskiaikainen linna, Moderni pilvenpiirtäjä
Abstraktit muodot	Kolmiot, Spiraalit, Geometriset kuviot
Elementtien määrä	Yksi objekti, Useita objekteja
Sääolosuhteet	Sade, Lumisade, Ukkonen, Sumu

Asema / Suunta	Ylhäällä, Keskellä, Alhaalla
Taiteellinen tyyli	Vesivärit, Maalaus, Matala-poly
Kuvan tarkkuus	Terävä, Pehmeä, Sumennettu
Kuvan laatu	Korkearesoluutio, Matalaresoluutio
Taustatila	Selkeä, Yksinkertainen, Ylikuormitettu
Suhteet / Mittasuhteet	Normaalit, Liioitellut, Pienennetyt
Toiminta	Kävelevä, Hyppäävä, Lentävä
Rungon asento	Pysty, Makuuasento, Kyykyssä
Kasvojen ilme	Iloinen, Surullinen, Yllättynyt
Symbolinen merkitys	Toivo, Pelko, Onnellisuus
Kuvakulma	Lähikuva, Laajakulma, Kaukokuva
Tila / Sijainti	Merenpinnan alla, Vuoren huipulla
Esineet ja asiat	Hehkuva pallo, Lasi, Kirja
Liike / Dynaamisuus	Staattinen, Liikkuva, Värähtelevä
Taiteen laji	Abstrakti taide, Surrealismi, Käsitetaide
Välineet	Siveltimen vedot, Lyijykynä, Vektorikuva
Esteettisyys	Minimalistinen, Ylellinen, Retro
Skaala / Suhde	Ylisuuri, Ylisuuri, Minimaalinen
Epätäydellisyys	Halkeamat, Kuluneet reunat, Säröt
Inhimillisyys	Inhimilliset virheet, Luonnollinen tunne
Abstraktit käsitteet	Aika, Älykkyys, Unelma
Kuvakulman tehosteet	Kalansilmä, Liikkuva kamera, Pyörivä kamera
Valon lähde	Auringonvalo, Kynttilänvalo, Keinovalo
Siluetti	Tumma hahmo, Varjokuva, Siluettikuva
Eläinten tyyli	Piirretty, Realistinen, 3D-malli
Kuvasuhde	16:9, 1:1, 4:3

Ikä









Aikamäärittely





Opetettu pilvi-materiaali



Prompt: cloud that looks like cow, blue sky, photo

Opetettu haamu-materiaali



Prompt: transparent ghost cow in the middle of the street, busy town, night time



Prompt: a transparent ghost slimer ghostbusters at night

Omat tekoälymallit









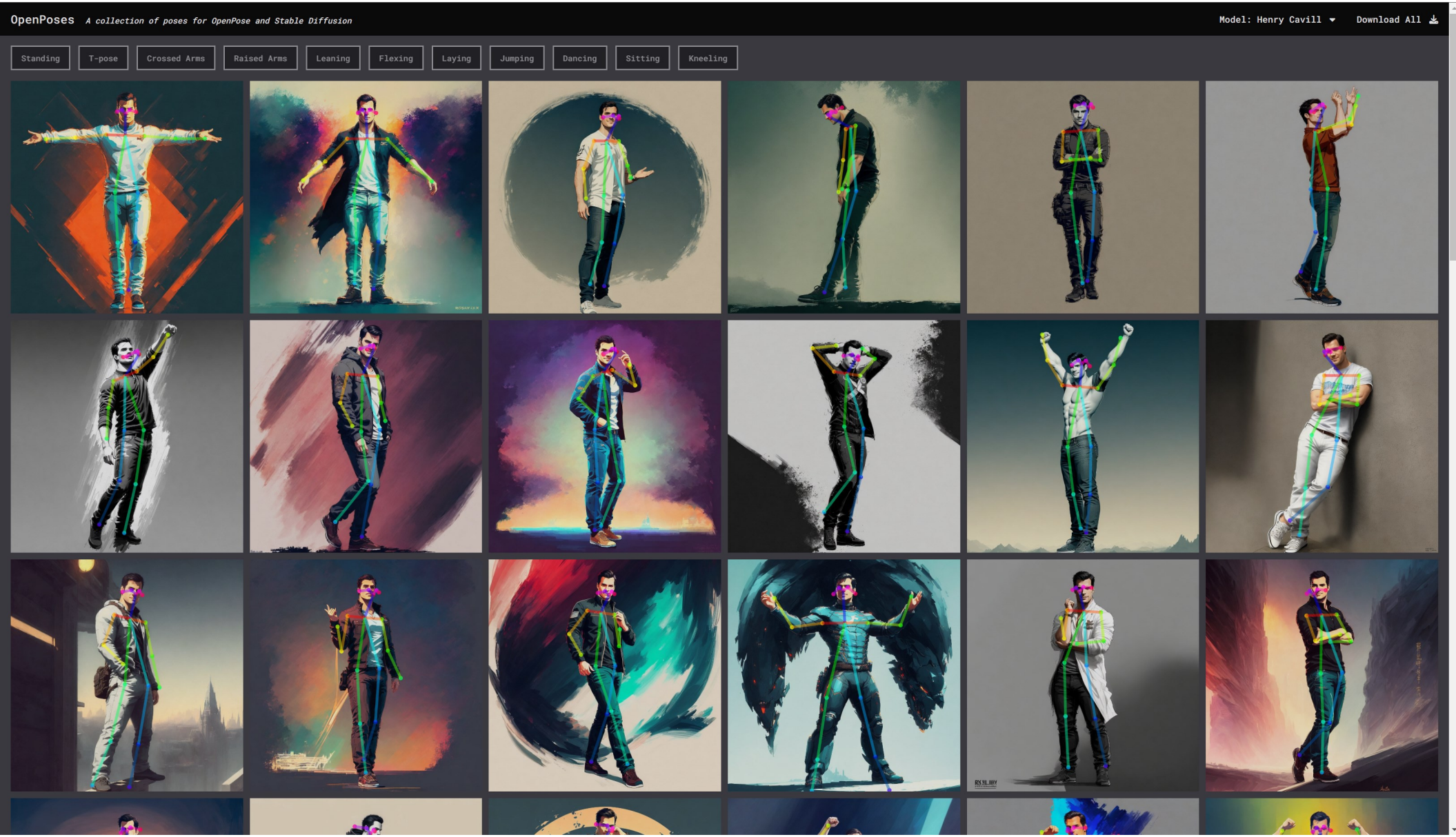




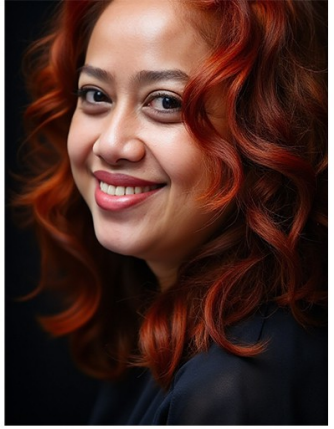
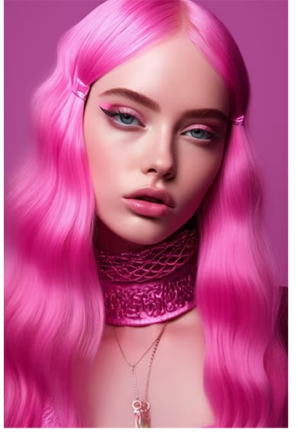
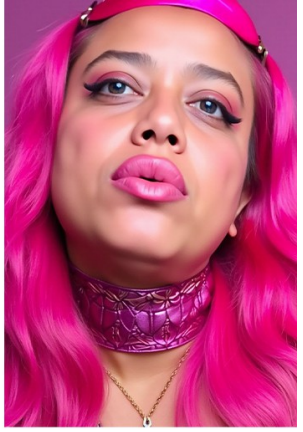


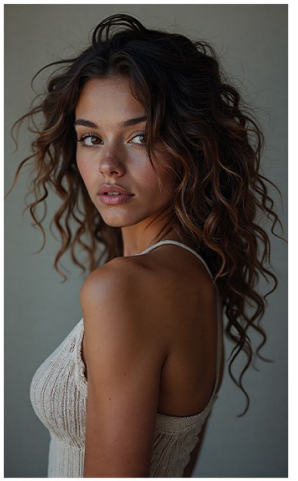
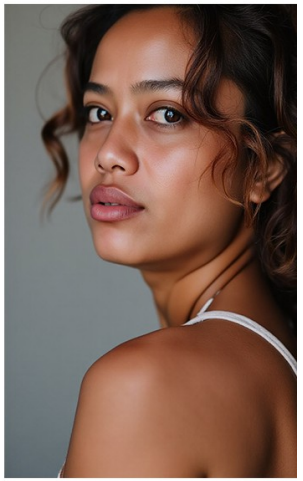


Asennot (OpenPose)










Tuotekuvat



Tuotekuvat

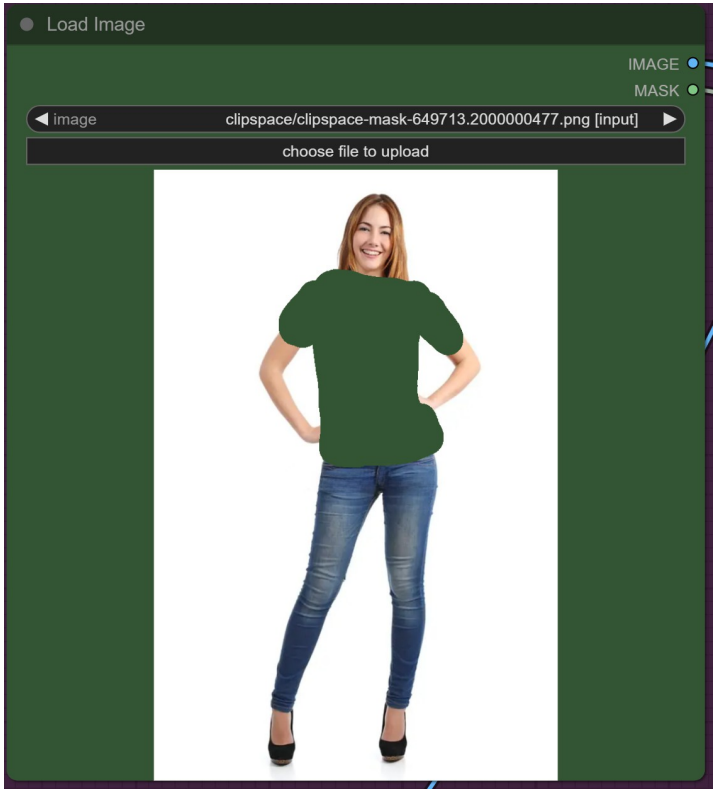


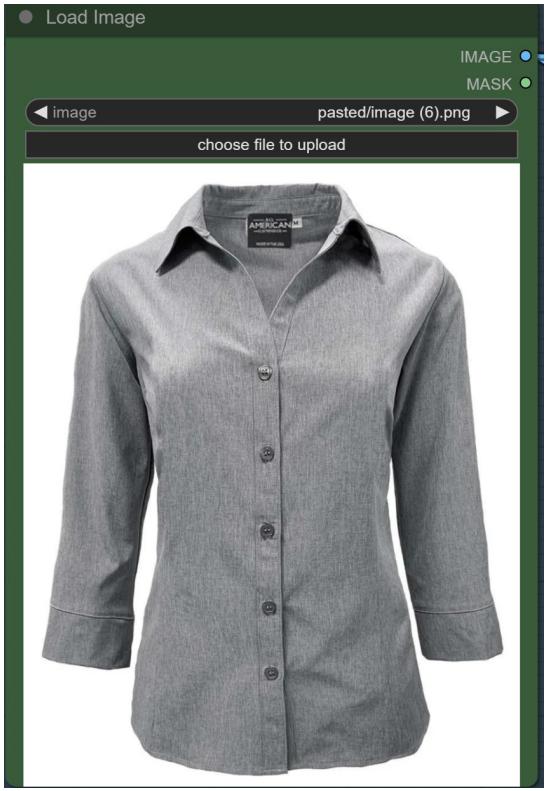






Virtuaalipukeutuminen (TryOn)

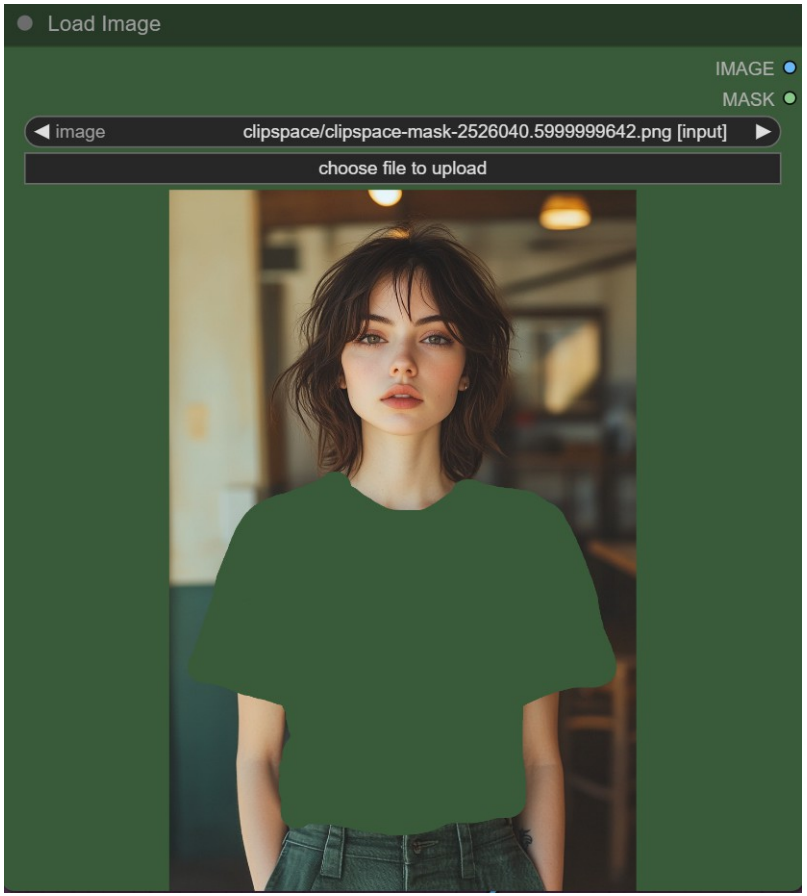






Virtuaalipukeutuminen (TryOn)







Virtuaalipukeutuminen (TryOn)





Lisätään kuvaan elementti (inpaint)



- Prompt: small town street on evening, cinematic

Lisätään kuvaan elementti (inpaint)



- Prompt: man walking

Lisätään kuvaan elementti (inpaint)



Kuvan laajennus (outpaint)



Kuvan laajennus (outpaint)









Kuvan laajennus (outpaint)



Kuvan laajennus (outpaint)



Kuvan laajennus (outpaint)



Materiaalin muuttaminen





Materiaalin muuttaminen



Materiaalin muuttaminen



Virtuaalilavastus / Sisustussuunnitelu





Virtuaalilavastus



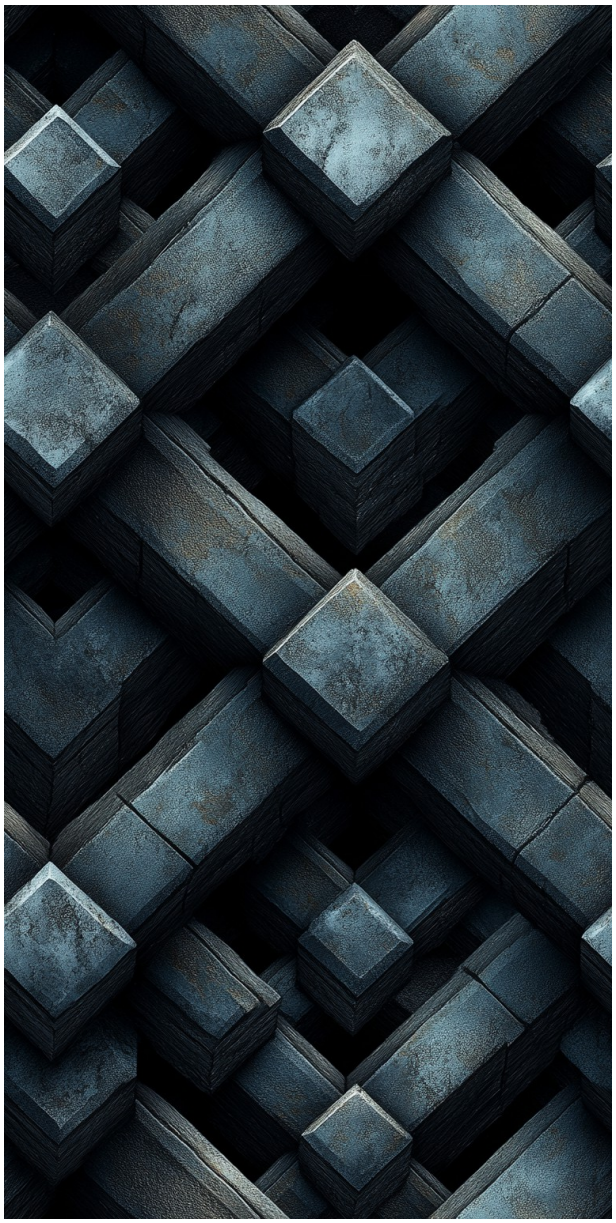
Virtuaalilavastus / Sisustussuunnitelu



Patternit







Patternit



Logo suunnittelu










Prompt: vector-style logo design for a modern coffee shop. The design should be clean, minimal, and use clever negative space in the style of Lindon Leader. The logo should prominently feature an abstract coffee bean, with smart use of negative space to reveal a hidden element such as a cup, steam, or a subtle coffee-related shape. The design should be bold, simple, and work perfectly in monochrome (black and white). Prioritize smooth, precise shapes, symmetry, and visual balance. Avoid gradients, unnecessary details, or 3D effects. No text. --no gradients, no complex shading, no cartoonish details, no unnecessary decorations --style raw --stylize 450 --v 6.1

Elokuvien kuvituskuvat













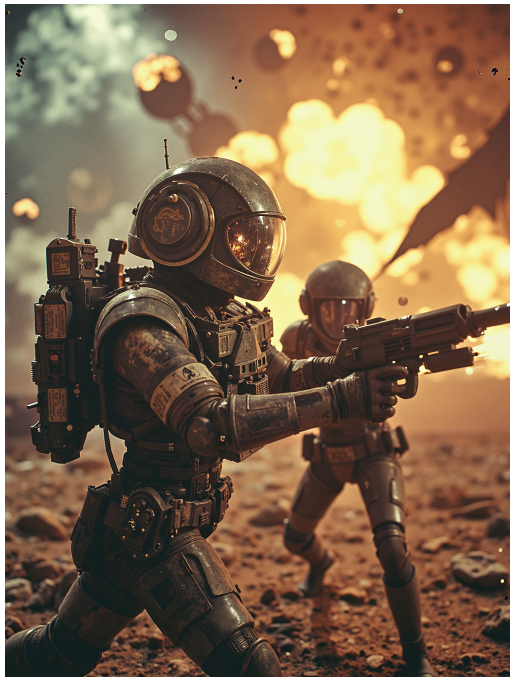




Elokuvien kuvituskuvat










AI Videot



AI Videot

- Tavat tehdä videoita:
  - Prompt: mies katsoo kameraan 2 sekunttia, kävelee poispäin kamerasta
  - Text to video
  - Image to video
  - Video to video
- Työkaluja kuten:
  - Kling AI (Lipsync)
  - OpenAI Sora 2 (vaatii VPN USA)
  - Google VEO 3.1

Minimax Hailuo

Hailuo AI

70 Subscribe for more credits

Image to Video | Text to Video

Favourites only

A cinematic, realistic scene on the surface of the moon, , star-filled sky. The iconic setting includes amplifier, electric guitar slightly dusted on lunar soil. A Finland flag stands proudly planted next to the setup, waving gently in the low lunar gravity. In the background, Earth rises over the horizon, casting a soft, blue glow across the surreal, silent moonscape, adding a sense of awe to the scene



Prompt

A cinematic, realistic scene on the surface of the moon, , star-filled sky. The iconic setting includes amplifier, electric guitar slightly dusted on lunar soil. A Finland flag stands proudly planted next to the setup, waving gently in the low lunar gravity. In the background, Earth rises over the horizon, casting a soft, blue glow across the surreal, silent moonscape, adding a sense of awe to the scene

T2V-01 Enable Optimization

Re-Create



Model

T2V-01
Base text-to-video model in 01 series

Quantity: 1

30

Prompt

A cinematic, realistic scene on the surface of the moon, , star-fille
amplifier, electric guitar slightly dusted on lunar soil. A Finland flag stands proudly planted next to

1 / 3

1 jobs in queue


Onko tämä helppoa?