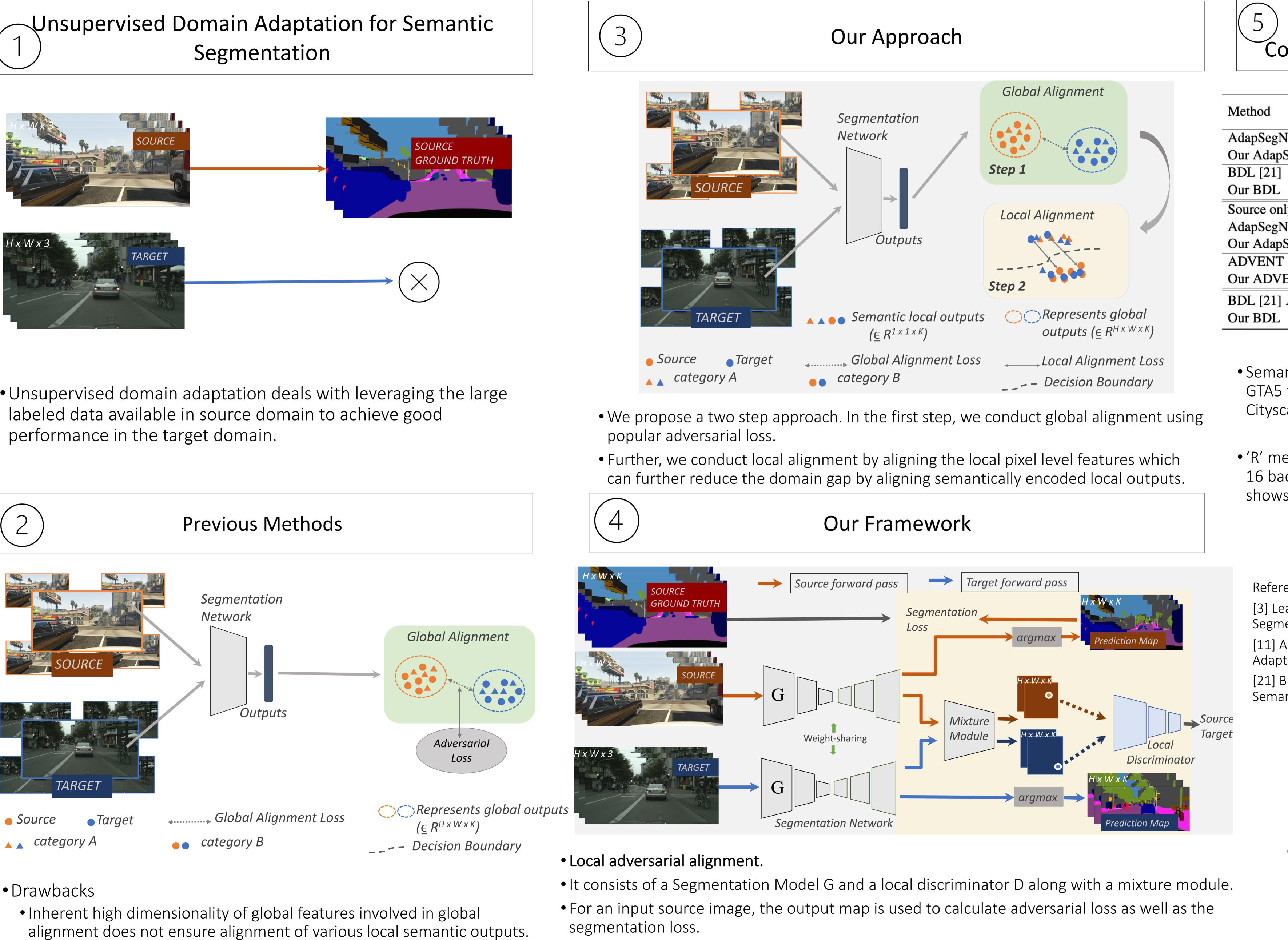
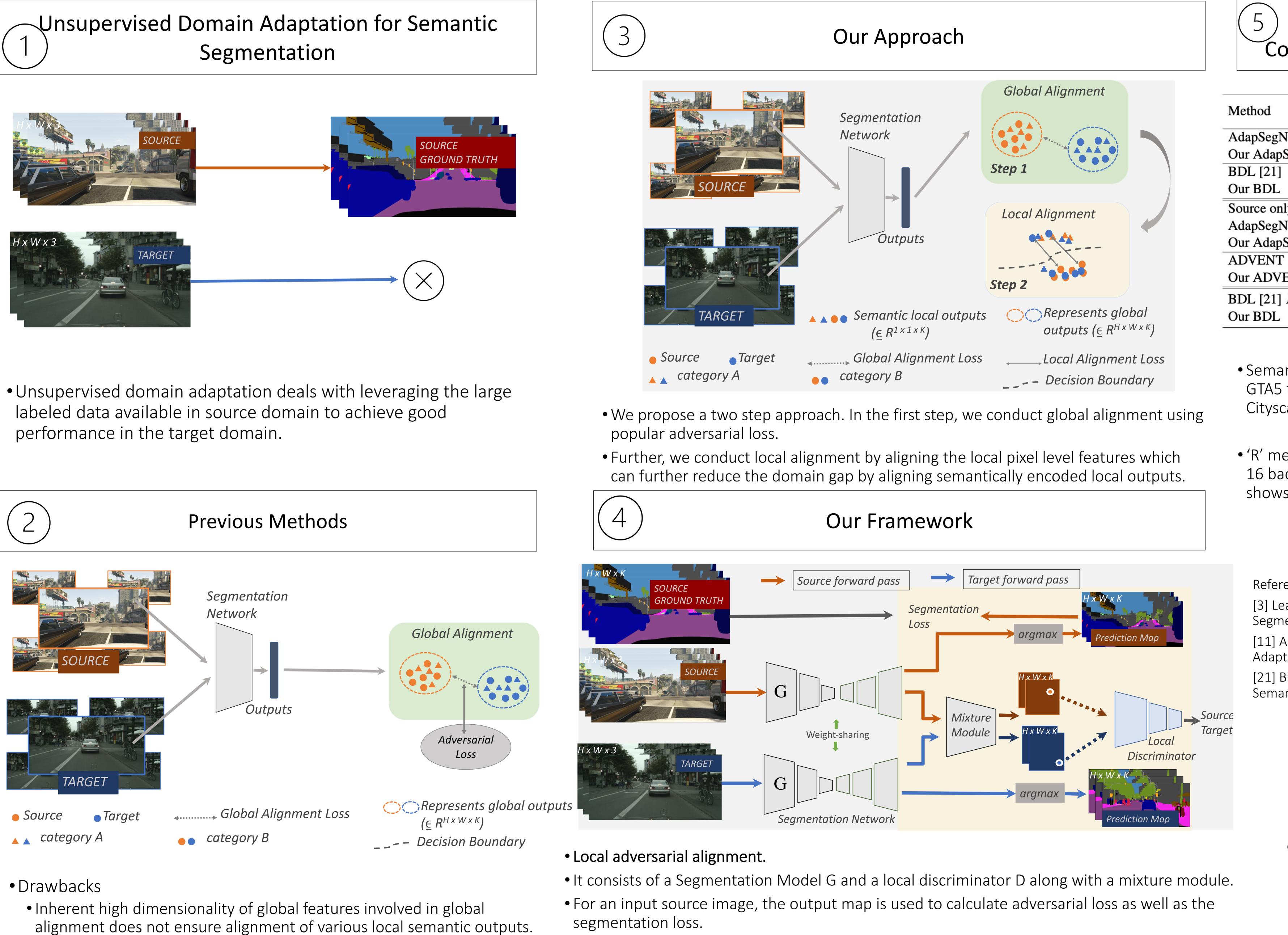


Segmentation





JOINT GLOBAL-LOCAL ALIGNMENT FOR DOMAIN ADAPTIVE SEMANTIC SEGMENTATION

Sudhir Yarram¹, Ming Yang², Junsong Yuan¹, Chuming Qiao¹ ¹University at Buffalo ²Horizon Robotics

• For an input target image, the output map is used to calculate the adversarial loss.

AdapSegNet Our AdapSeg Source only AdapSegNet Our AdapSeg **ADVENT** [1 Our ADVEN BDL [21] M

> Semantic segmentation performance in mIoU(%) on GTA5 to Cityscapes (GTA2City) and Synthia to Cityscapes (SYN2City) Adaptation task.

• 'R' means the ResNet-101 and 'V' means the VGG-16 backbone. Our global-local alignment approach shows consistent improvement over baselines.

References: [3] Learning to Adapt Structured Output Space for Semantic Segmentation, CVPR'18 [11] ADVENT: Adversarial Entropy Minimization for Domain Adaptation in Semantic Segmentation, CVPR'19 [21] Bidirectional Learning for Domain Adaptation of Semantic Segmentation, CVPR'19

Github: github.com/skrya/globallocal





Horizon **Robotics**

Experiments: Comparison with state-of-the-arts

	Arch.	GTA2City	SYN2City
		mIoU(%)	mIoU(%)
et [3]	V	35.0	37.6
egNet	V	$\textbf{36.8} \pm \textbf{0.2}~\textbf{(+1.8)}$	$\textbf{38.9}\pm\textbf{0.3}~\textbf{(+1.3)}$
	V	41.3	46.1
	V	$\textbf{43.5}\pm\textbf{0.2}~\textbf{(+2.2)}$	$\textbf{47.7} \pm \textbf{0.2} ~ \textbf{(+1.6)}$
7	-	36.6	38.6
et [3]	R	41.4	45.9
egNet	R	$\textbf{45.2} \pm \textbf{0.1} ~ \textbf{(+3.8)}$	$\textbf{46.9} \pm \textbf{0.3}~\textbf{(+1.0)}$
11]	R	43.8	47.6
NT	R	$\textbf{46.4} \pm \textbf{0.3}~\textbf{(+2.6)}$	$\textbf{48.3} \pm \textbf{0.4} \textbf{ (+0.7)}$
$M_2^{(2)}(F^{(2)})$	R	48.5	51.4
/	R	$\textbf{49.4} \pm \textbf{0.2}~\textbf{(+0.9)}$	$\textbf{52.5} \pm \textbf{0.3} ~ \textbf{(+1.1)}$