IOS INSTITUT FÜR OPTISCHE SYSTEME

HTWG Hochschule Konstanz Technik, Wirtschaft und Gestaltung

Bundesministerium für Bildung und Forschung

VDI

Universität Konstanz

# Geometric Deep Learning

*Brown-Bag-Seminar 2019, IOS, Konstanz*

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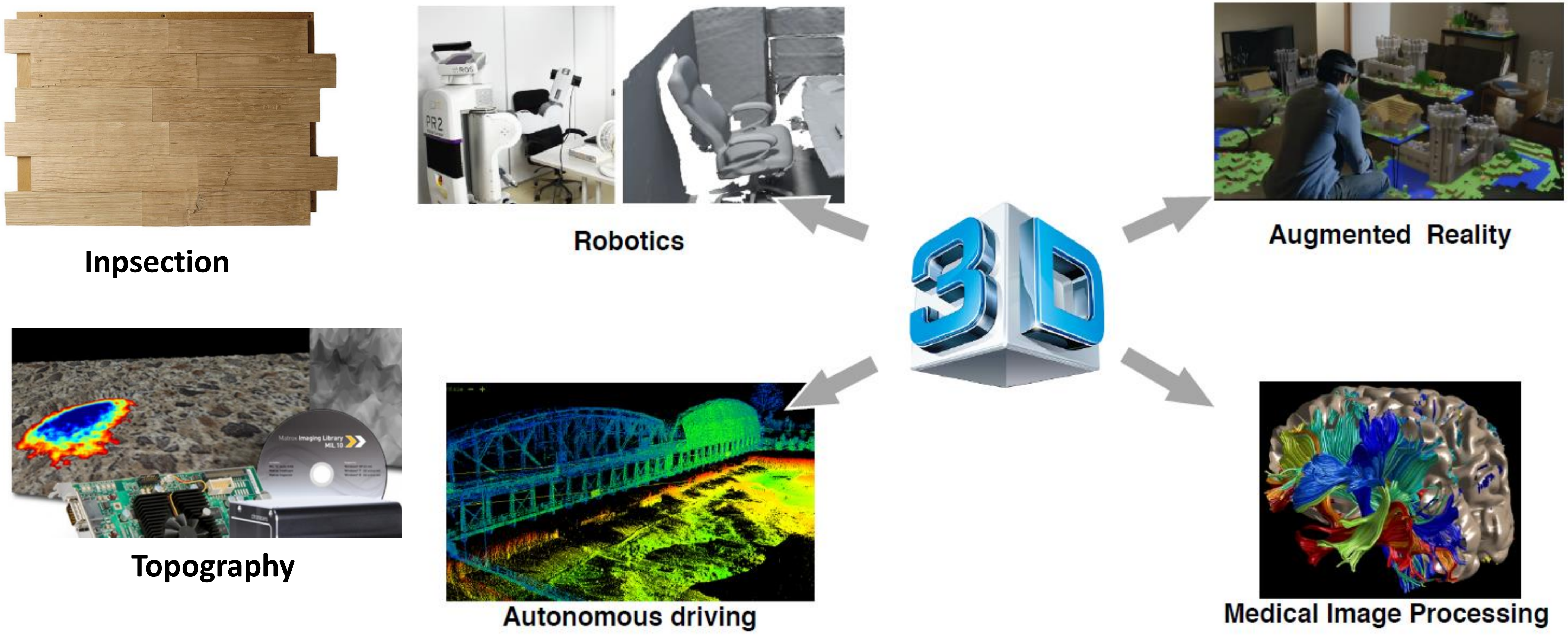
BMBF-FZ: 13N14540

# Contents

- Why geometric deep learning?
- Limits of traditional Convolutional Neural Networks
- Machine Learning on non-Euclidean domains
    - Meshes a.k.a 2-manifolds
    - General graphs
    - Point clouds a.k.a. Sets
- A Common Framework

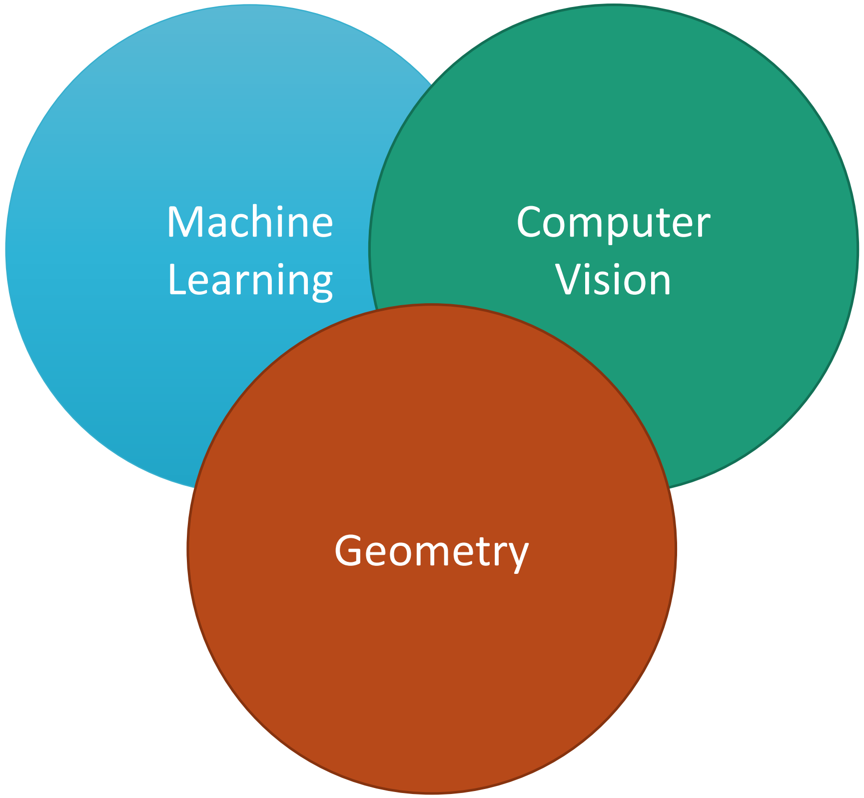
# A lot of visual data is not flat




Credits to Hao Su, Stanford 2017

# The surge of geometric deep learning

- Started 2015 with big datasets ShapeNet & ModelNet
- Very active due to huge industry interests



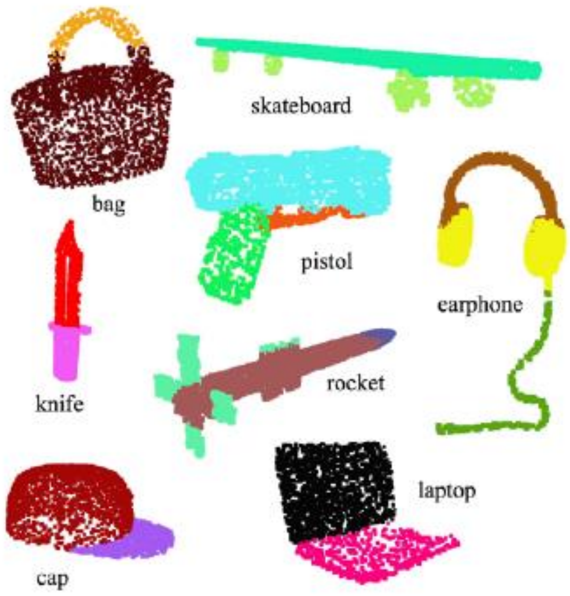

Industries are:

- Robotics
- 3d scanning
- 3d geometric modelling
- Autonomous driving
- Augemented reality
- Virtual reality
- Topography
- Etc.

# 3d deep learning tasks

## 3D geometry analysis


Classification




Parsing
(object/scene)

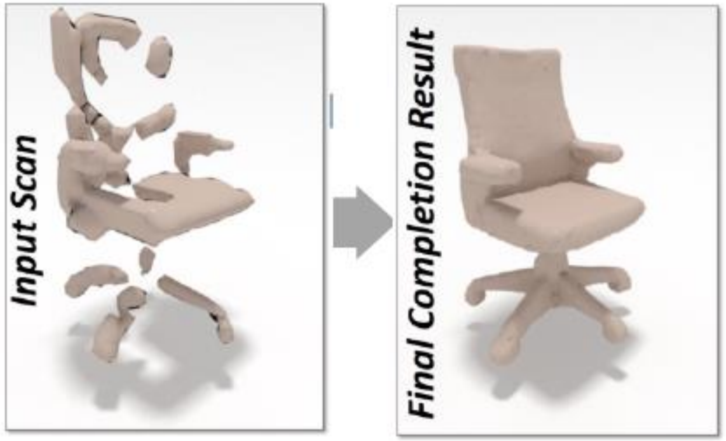
Correspondence

Credits to Hao Su, Stanford 2017

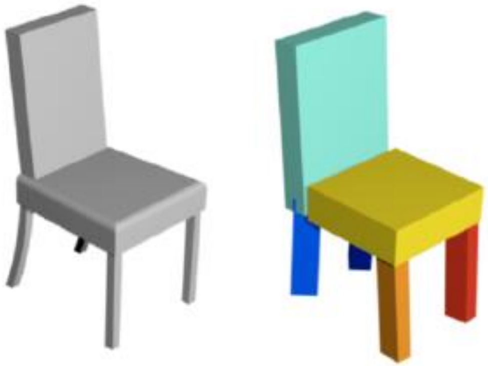
# 3d deep learning tasks

## 3D synthesis

Monocular
3D reconstruction



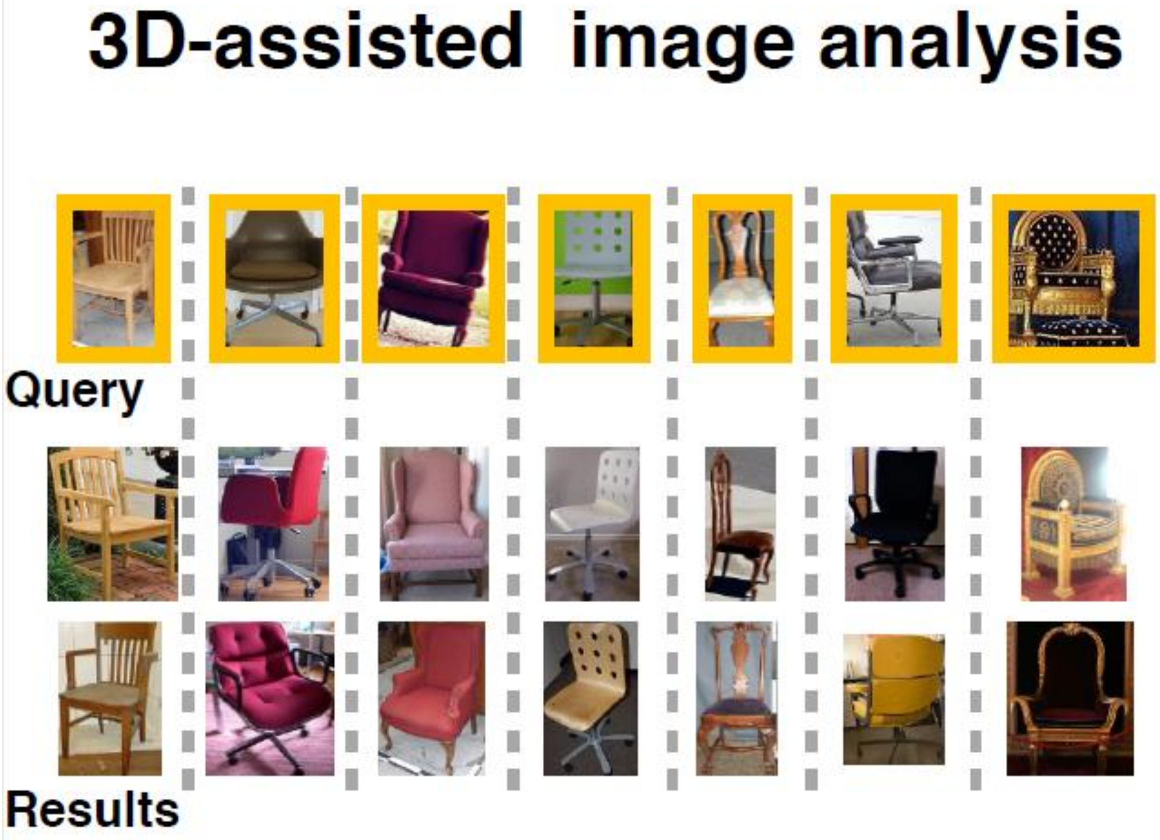

Shape completion



Shape modeling

Credits to Hao Su, Stanford 2017

# 3d deep learning tasks



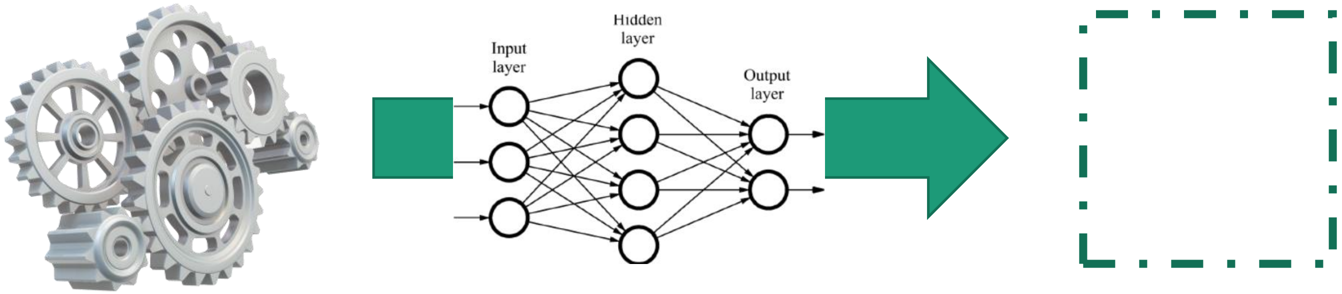

Cross-view image retrieval

Intrinsic decomposition

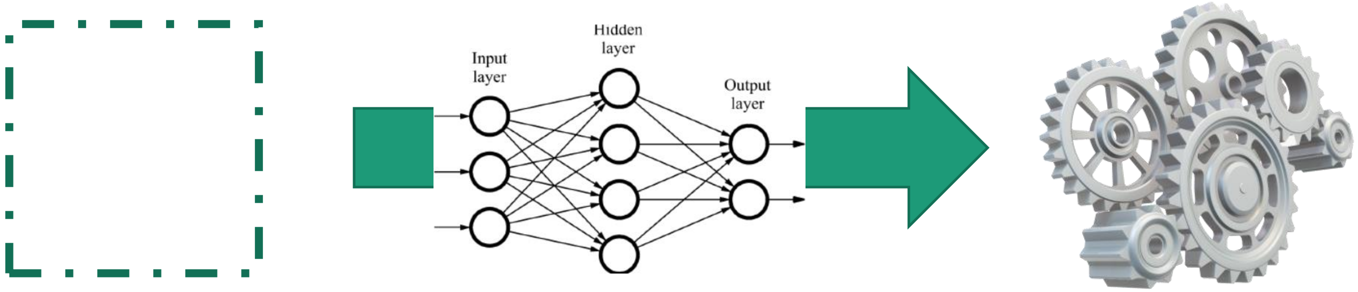
Credits to Hao Su, Stanford 2017

# The data vs. the network

**Geometry analysis**




**Geometry synthesis**



# Convolution Neural Networks. Where is the problem?

**Images have a very easy regular data structure!**

- Unique representation
  → easy (e.g. flatten())
- Vector representation
  → easy (e.g. flatten())
- Distance and dot product
  → easy (e.g. $||X - Z||_2 \ or < X, Y >$ )
- Functional representation
  → easy (f: $[0,1]^2 \rightarrow \mathbb{R}$)
- Subsampling
  → easy (e.g. X[0::2])

| | | | | | | | |
|---|---|---|---|---|---|---|---|
| 1 | 44 | 33 | 12 | 20 | 23 | 35 | 14 |
| 51 | 16 | 40 | 32 | 46 | 48 | 28 | 17 |
| 29 | 60 | 3 | 63 | 49 | 55 | 36 | 7 |
| 52 | 22 | 26 | 41 | 38 | 10 | 61 | 53 |
| 2 | 24 | 19 | 11 | 34 | 43 | 5 | 8 |
| 57 | 9 | 37 | 42 | 25 | 21 | 27 | 18 |
| 30 | 56 | 50 | 64 | 4 | 59 | 6 | 13 |
| 58 | 47 | 45 | 31 | 39 | 15 | 62 | 54 |

# Euclidean vs. Non-Euclidean data

Images, text, audio, and others can be treated as Euclidean data (little inductive bias).

Non-Euclidean data can represent more complex items and concepts (extreme inductive bias).

7

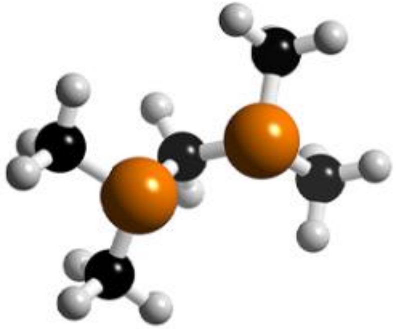
Numbers


Images

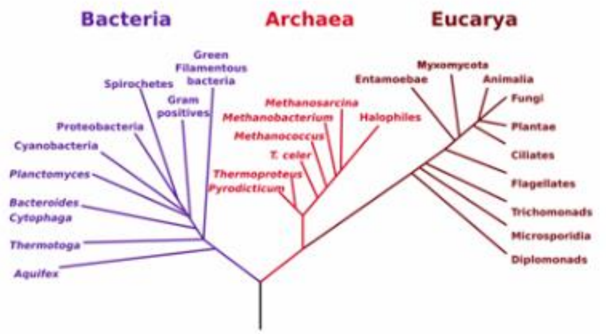
The quick brown fox jumps over the lazy dog

Text

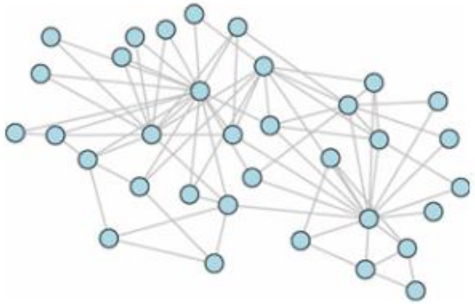
Audio



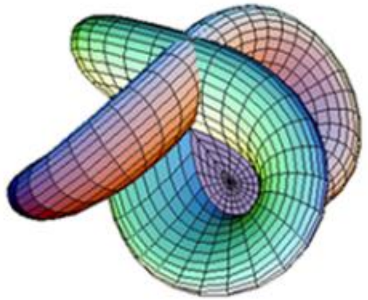
Molecules




Trees



Networks

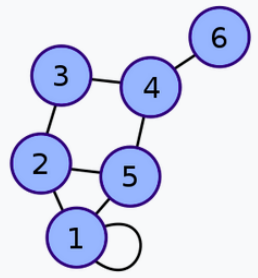


Manifolds

# Graph representation

Set of points + adjacency matrix + optional vertex attributes

| | | |
|---|---|---|
| -0.180226841 | 0.360945118 | -1.120304970 |
| -0.180226841 | 1.559292118 | -0.407860970 |
| -0.180226841 | 1.503191118 | 0.986935030 |
| -0.180226841 | 0.360945118 | 1.29018350 |
| -0.180226841 | -0.781300882 | 0.986935030 |
| -0.180226841 | -0.837401882 | -0.407860970 |
| -0.180226841 | 0.360945118 | -2.206546970 |
| -0.180226841 | 2.517950118 | -0.917077970 |
| -0.180226841 | 2.421289118 | 1.572099030 |
| -0.180226841 | -1.699398882 | 1.572099030 |
| -0.180226841 | -1.796059882 | -0.917077970 |

| Labeled graph | Adjacency matrix |
|---|---|
|  | $\begin{pmatrix} 2 & 1 & 0 & 0 & 1 & 0 \\ 1 & 0 & 1 & 0 & 1 & 0 \\ 0 & 1 & 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 & 1 & 1 \\ 1 & 1 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 \end{pmatrix}$ Coordinates are 1–6. |



| | | |
|---|---|---|
| -0.180226841 | 0.360945118 | -1.120304970 |
| -0.180226841 | 1.559292118 | -0.407860970 |
| -0.180226841 | 1.503191118 | 0.986935030 |
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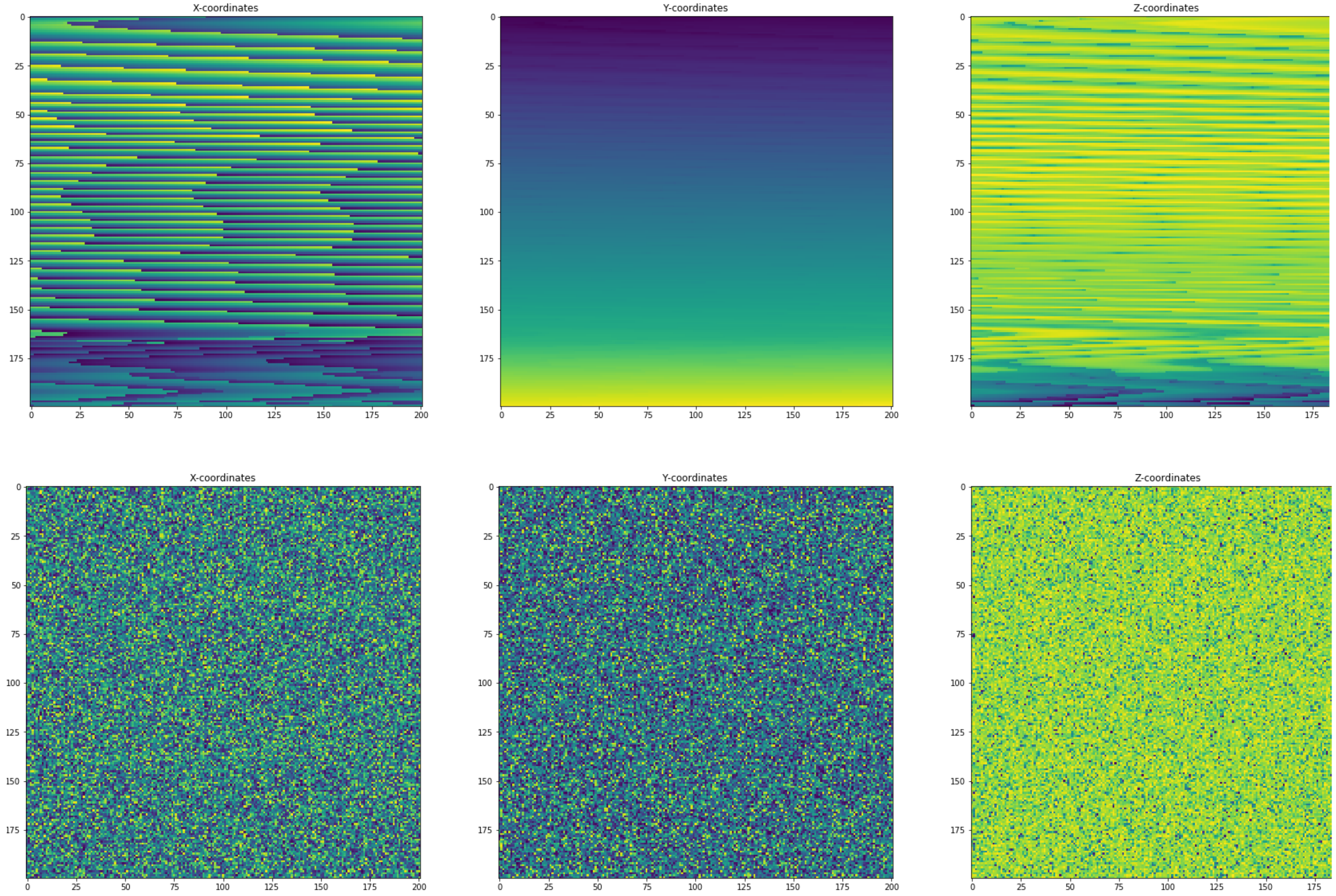
| -0.180226841 | -0.781300882 | 0.986935030 |
| -0.180226841 | -0.837401882 | -0.407860970 |
| -0.180226841 | 0.360945118 | -2.206546970 |
| -0.180226841 | 2.517950118 | -0.917077970 |
| -0.180226841 | 2.421289118 | 1.572099030 |
| -0.180226841 | -1.699398882 | 1.572099030 |
| -0.180226841 | -1.796059882 | -0.917077970 |

**Adjacency matrix is either given or induced by metric (e.g. through k-nearest neighbors search)!**

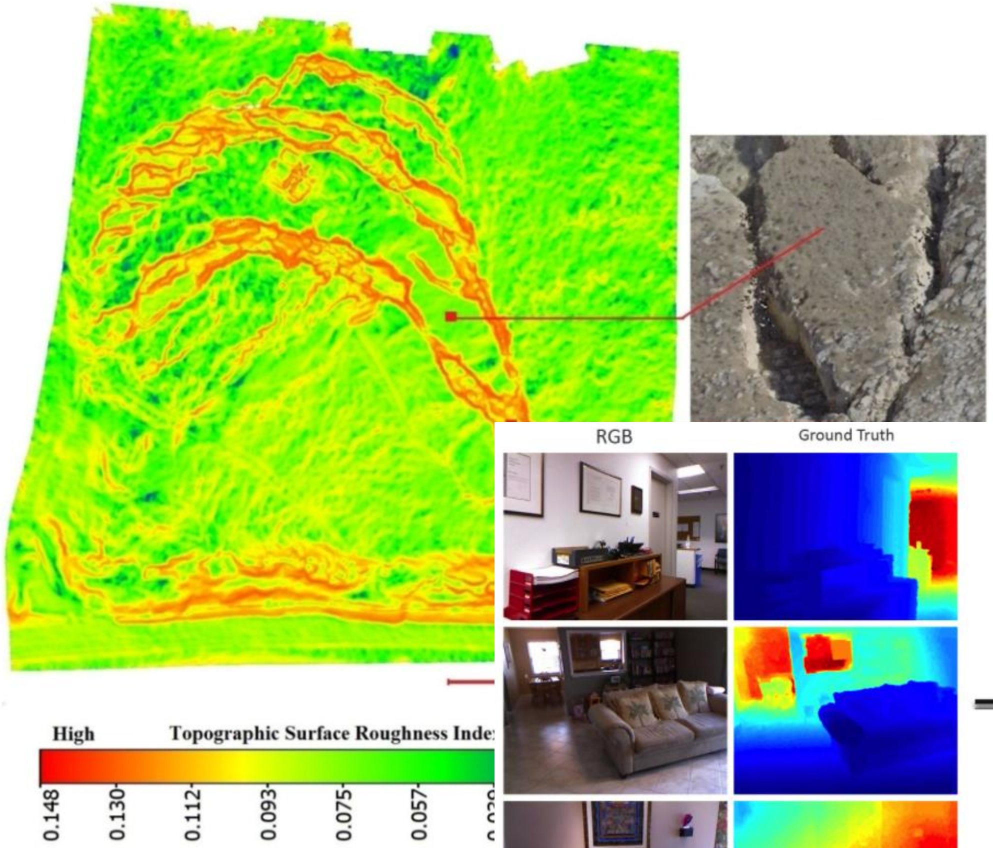
# Order matters (not): Stanford bunny example

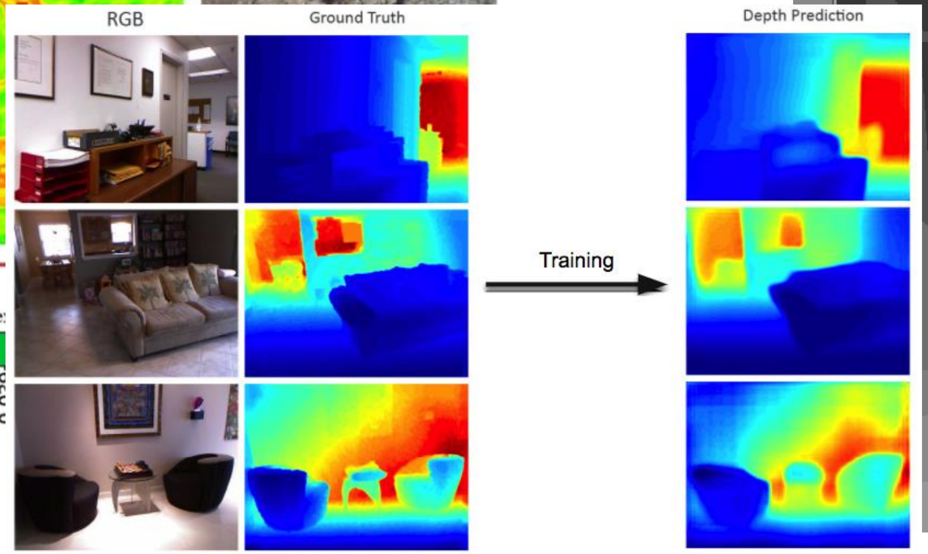



2d coordinate maps of the Stanford bunny in scanning order (top) and arbitrary order (bottom).

In unstructured 3d data order is arbitrary.

# Statistics matters: Topographic and depth maps




Depth maps are structured and look like images, but have rougher local structures and smoother global structures (different image statistics compared to natural images).

Credits: https://www.mdpi.com/remotesensing/remotesensing-08-00095/

# Convolution Neural Networks on grids

## Convolution

| | | | | | | | |
|---|---|---|---|---|---|---|---|
| 1 | 44 | 33 | 12 | 20 | 23 | 35 | 14 |
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| 29 | 60 | 3 | 63 | 49 | 55 | 36 | 7 |
| 52 | 22 | 26 | 41 | 38 | 10 | 61 | 53 |
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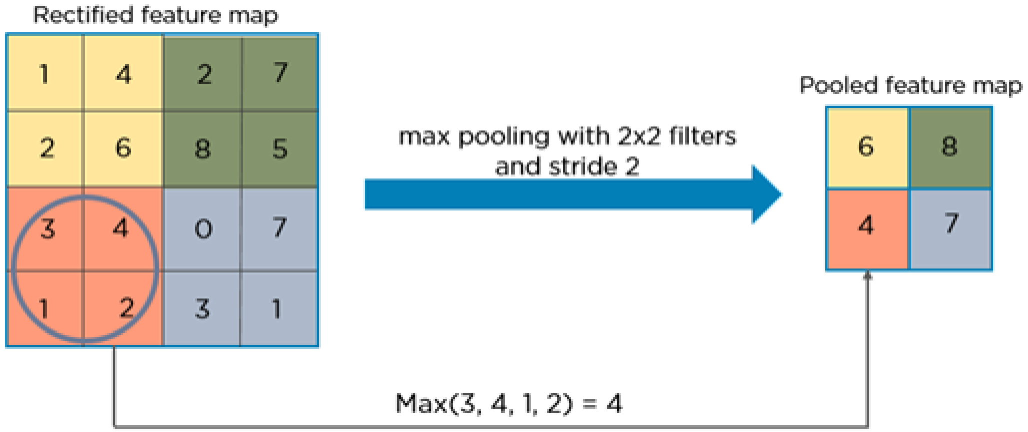
| 57 | 9 | 37 | 42 | 25 | 21 | 27 | 18 |
| 30 | 56 | 50 | 64 | 4 | 59 | 6 | 13 |
| 58 | 47 | 45 | 31 | 39 | 15 | 62 | 54 |

## Pooling



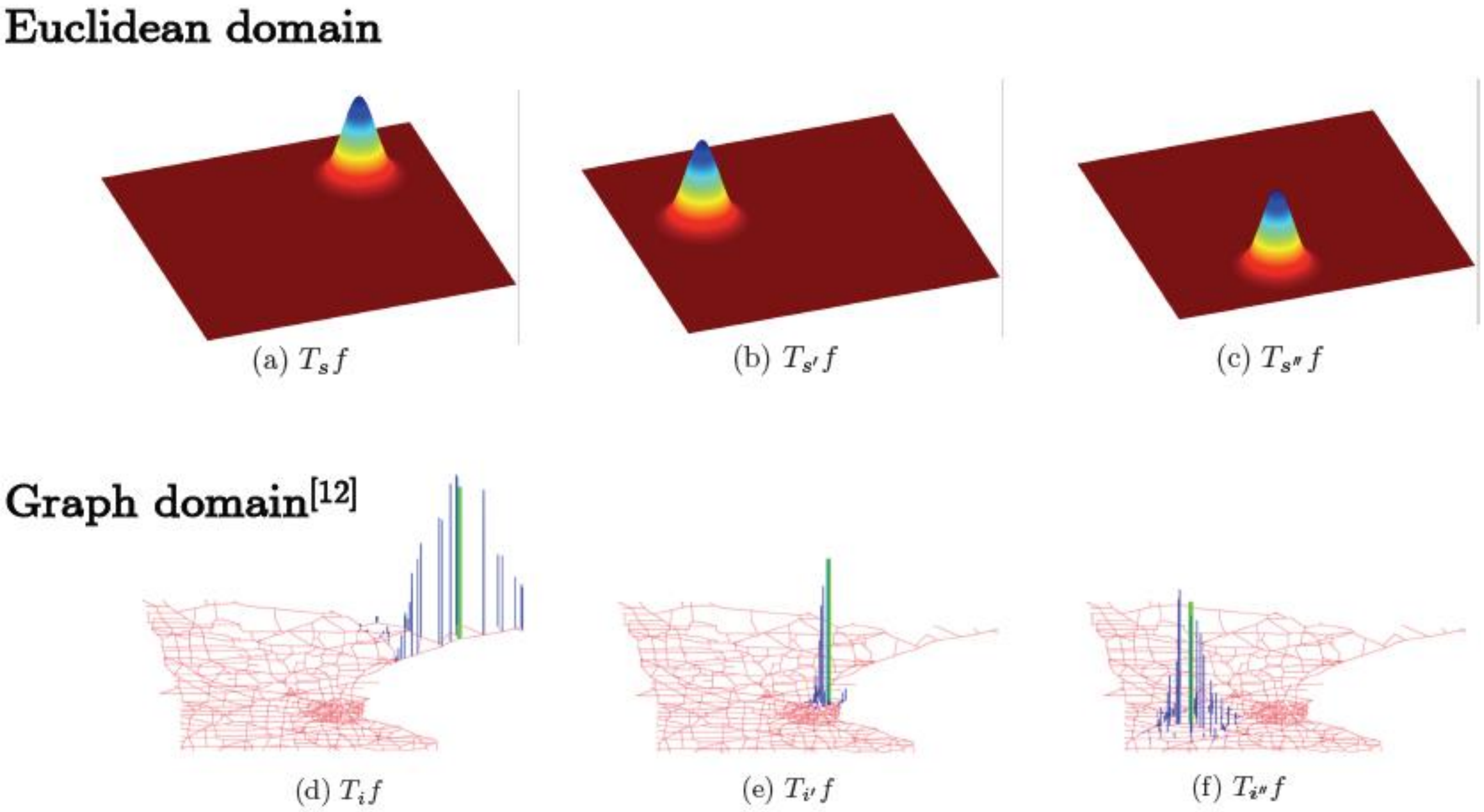

$$(f * g)[x] = \sum_{-M}^{M} f[n-m]g[m]$$

Both operations need an **underlying structure** like defined neighborhoods, directions, order, translations and common vector space!

→ Image are **flat**, i.e. have a flat metric (not curved)

→ Images have a **homogenous topology** (every pixel has the same neighborhood)

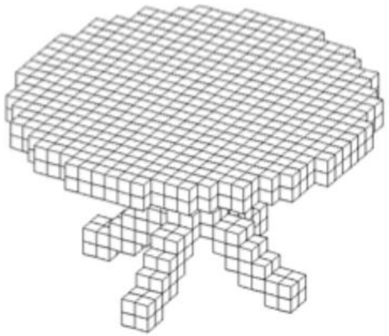
# No shift invariance on graphs

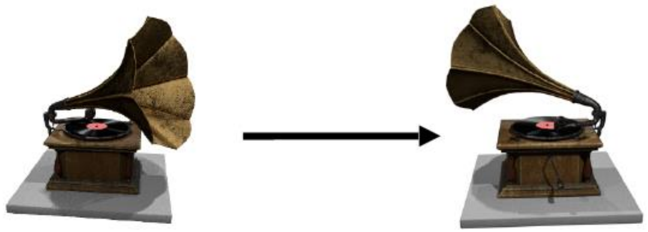



Credits to Shuman et. al., 2016

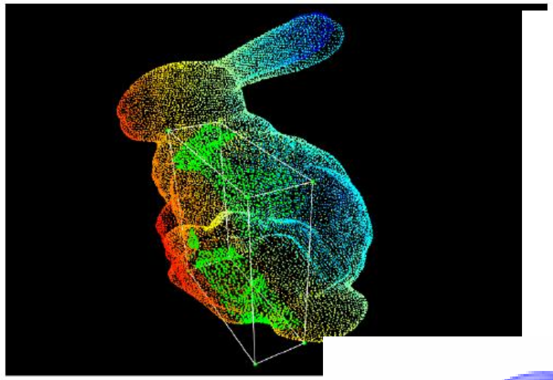
# Different 3d data representations

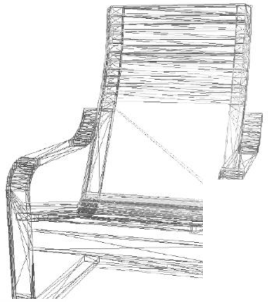
- **Rasterized form (regular)**
  - Multi-view RGB(D) images
  - volumetric

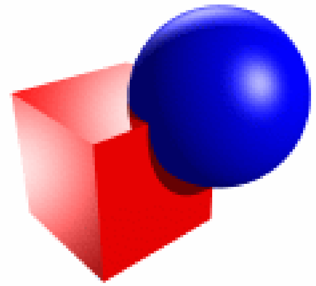


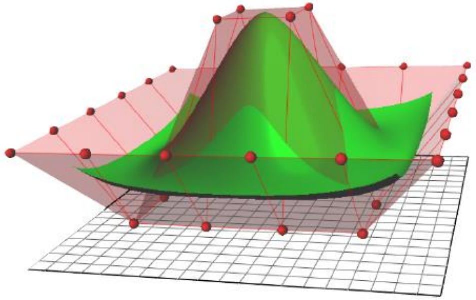


- **Geometric form (irregular)**
  - Polygon mesh / wire frame
  - Point cloud
  - Parametric surfaces
  - Primitive based CAD (CSG)







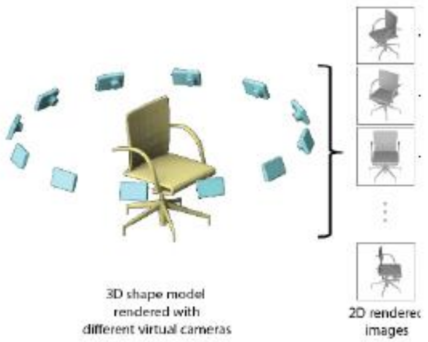


# Different 3d data representations

- **Rasterized form (regular)**
  - Multi-view RGB(D) images → Standard convolution and pooling operator
  - volumetric → Discrete 3d convolution and pooling operator

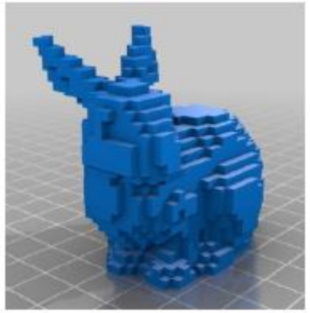
- **Geometric form (irregular)**
  - Polygon mesh / wire frame → e.g. no homogenous neighborhood
  - Point cloud → e.g. no canonical order
  - Parametric surfaces → e.g. no unique parametrization
  - Primitive based CAD (CSG) → e.g. no homogenous neighborhood

# Existing 3d learning algorithms



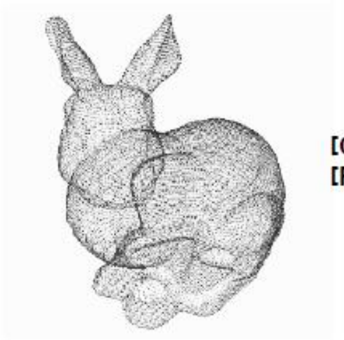

[Su et al. 2015]
[Kalogerakis et al. 2016]
...

Multi-view



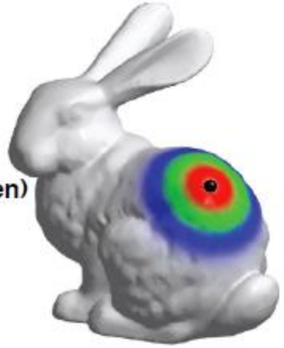
[Maturana et al. 2015]
[Wu et al. 2015] (GAN)
[Qi et al. 2016]
[Liu et al. 2016]
**[Wang et al. 2017] (O-Net)**
**[Tatarchenko et al. 2017] (OGN)**
...

Volumetric



**[Qi et al. 2017] (PointNet)**
**[Fan et al. 2017] (PointSetGen)**

Point cloud



[Defferard et al. 2016]
[Henaff et al. 2015]
**[Yi et al. 2017] (SyncSpecCNN)**
...

Mesh (Graph CNN)

**[Tulsiani et al. 2017]**
**[Li et al. 2017] (GRASS)**

Part assembly

# Deep Learning on 3d meshes

- *Math heavy approach, will be a standard deep learning tool, soon –*

# The math ingredients of meshes

**Manifolds**

**Sparse data structures**

**Differential geometry**

**Differential topology**

**Graph theory**

**Laplacian**

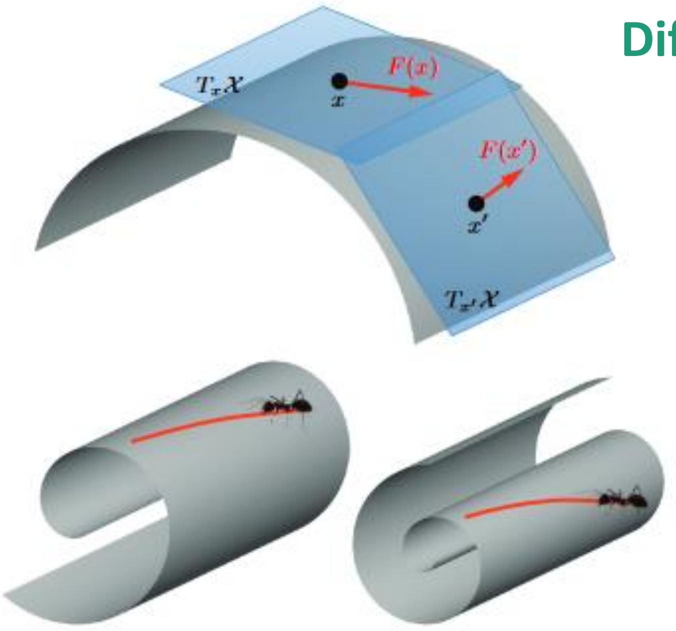



Fig. 1. Top: tangent space and tangent vectors on a two-dimensional manifold (surface). Bottom: Examples of isometric deformations.

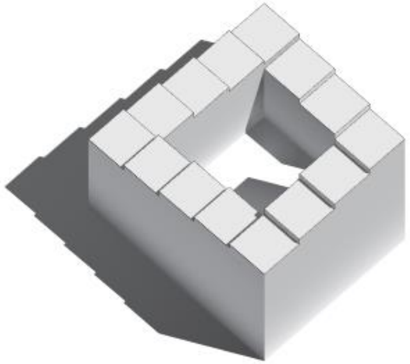


Geometric deep learning: going beyond Euclidean data

Michael M. Bronstein, Joan Bruna, Yann LeCun, Arthur Szlam, Pierre Vandergheynst

Many scientific fields study data with an underlying structure that is a non-Euclidean space. Some examples include social networks in computational social sciences, sensor networks in communications, functional networks in brain imaging, regulatory networks in genetics, and meshed surfaces ... the data such as stationarity and compositionality through local statistics, which are present in natural images, video, and speech [14], [15]. These statistical properties have been related to physics [16] and formalized in specific classes of convolutional neural networks (CNNs) [17], [18], [19]. In image ...

DISCRETE DIFFERENTIAL GEOMETRY: AN APPLIED INTRODUCTION

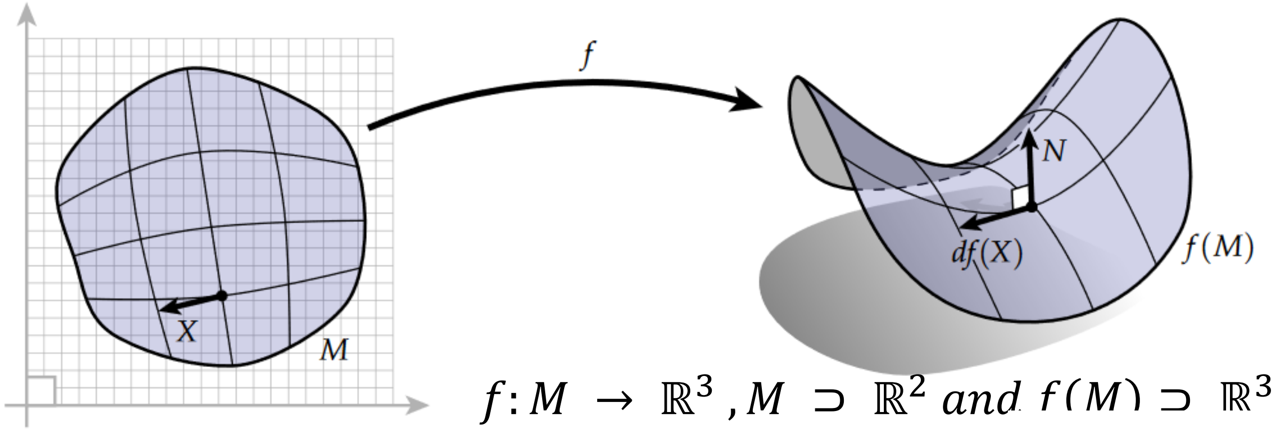


Keenan Crane

Credits to Michael Bronstein et. al., 2016 and Keenan Crane, 2019

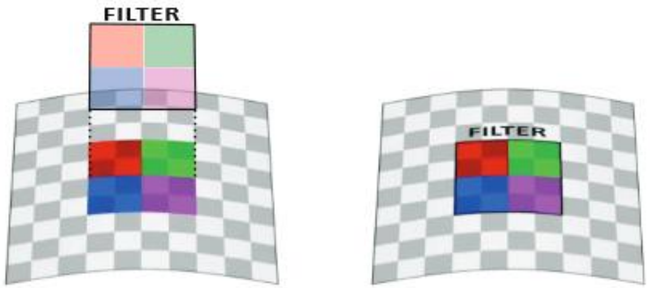
# Three strategies to define a convolution neural network on meshes

- RNNs (more like a brute force approach)
- Conduct convolution **on a parametrization** (typically 2d) of a mesh/graph (typically 3d)



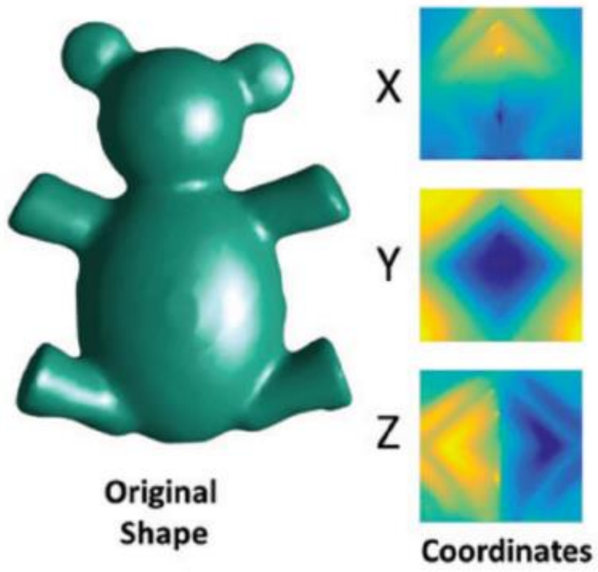

$f: M \to \mathbb{R}^3, M \supset \mathbb{R}^2$ *and* $f(M) \supset \mathbb{R}^3$

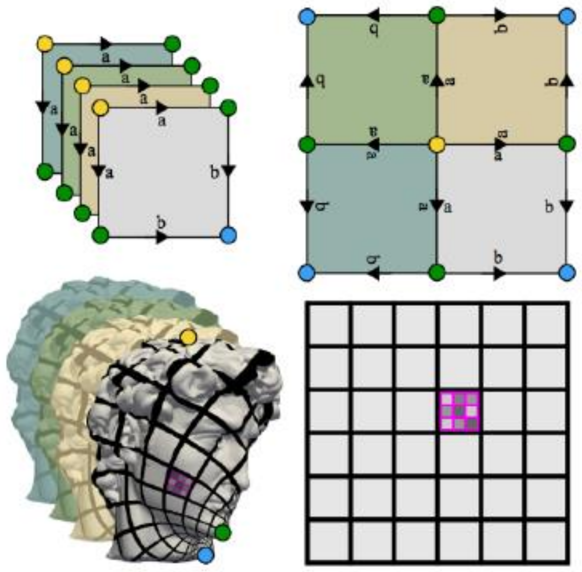
- Conduct convolution **on the mesh**



# Bringing 3d into Euclidean plane and proceed with traditional techniques

- Map curved 3D surfaces to 2D Euclidean plane



Ayan Sinha, Jing Bai, Karthik Ramani
**"Deep Learning 3D Shape Surfaces Using Geometry Images"**
*ECCV2016*

Maron et al.
**"Convolutional Neural Networks on Surfaces via Seamless Toric Covers'**
*SIGGRAPH2017*

# Desired properties for convolution without parametrization

- Translation invariant filters, i.e. weight sharing
- Localized, i.e. edge detector

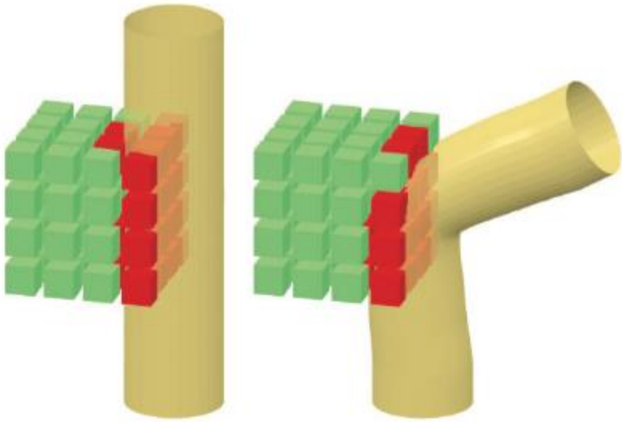


image credit: D. Boscaini, et al.

convolutional along spatial coordinates

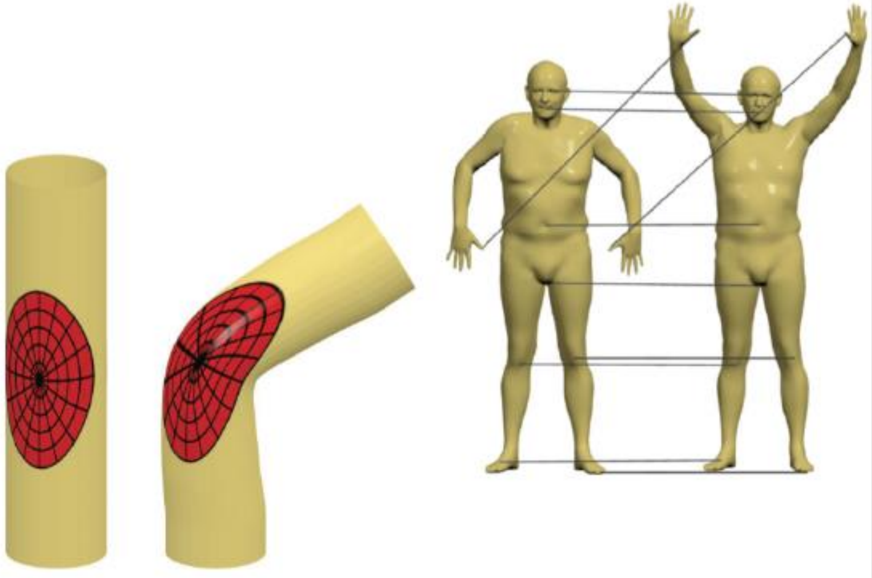
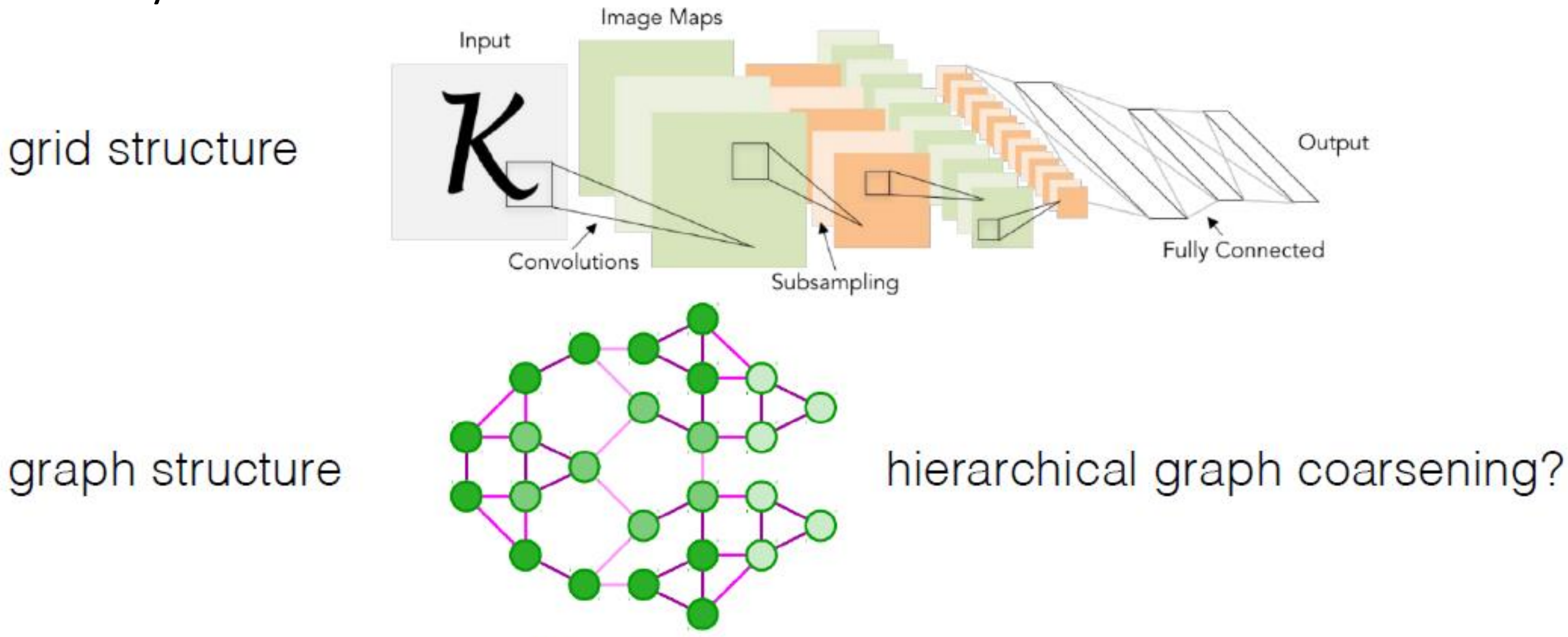


image credit: D. Boscaini, et al.

convolutional considering underlying geometry

# More inductive bias, please

- Receptive fields
- Multi-scale analysis

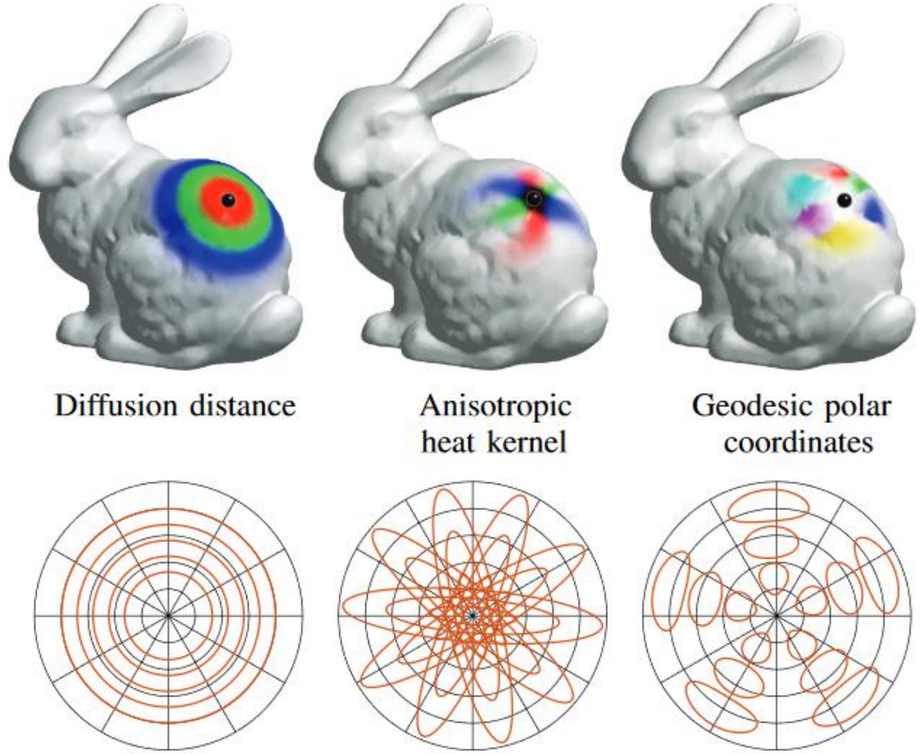


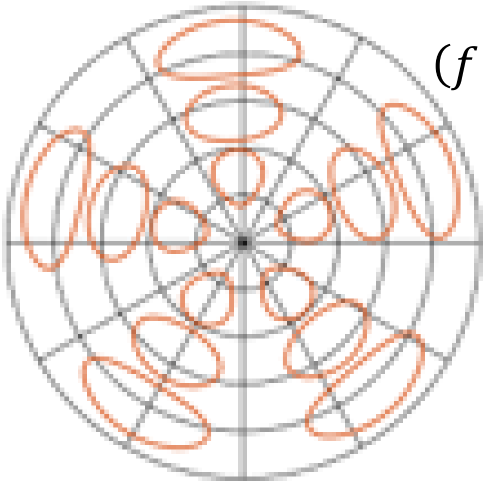

from Michaël Defferrard et al. 2016

Credits to Michael Deferrard et. al., 2016

# Geometry approach: Geodesic CNN

- Local system of geodesic polar coordinate
- Extract a small patch at each point x
- Compute response with a trainable patch-like filter



$$(f * g)[x] = \sum_{i}^{angles} \sum_{j}^{rings} g_{ij} D_{ij}(x) f$$

One weight g for all i*j basis function
In a local point specific
coordinate system

Credits to Jonathan Masci et. al., 2015

# Geometry approach: Geodesic CNN

- Direct encoding of the differential geometry
- The radius of the geodesic patches must be sufficiently small to acquire a topological disk
- No effective pooling, purely relying on convolutions to increase receptive field
- Slow because of huge tensors because of local of coordinate frames
- Limited to rotation invariant filters or curvature aligned filters

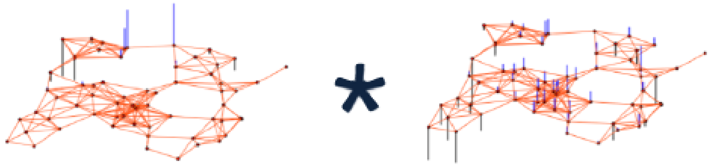
Credits to Jonathan Masci et. al., 2015

# Signal approach: Spectral CNN

Generalized convolution of $f, g \in L^2(X)$ can be defined by analogy

$$(f \star g)(x) = \underbrace{\sum_{k \geq 1} \underbrace{\langle f, \phi_k \rangle_{L^2(X)} \langle g, \phi_k \rangle_{L^2(X)}}_{\text{product in the Fourier domain}} \phi_k(x)}_{\text{inverse Fourier transform}}$$

**Generalized convolution allows spectral filtering!**



**The Laplace operator tells us something about curvature!**

**>> We can compute Eigenfunctions of the Laplacian**

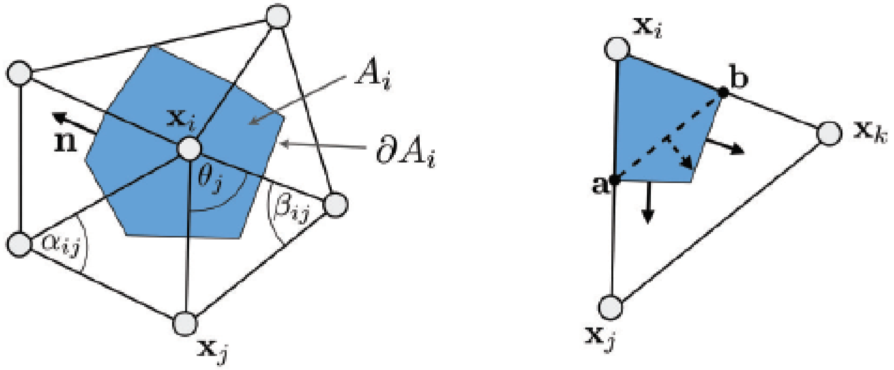
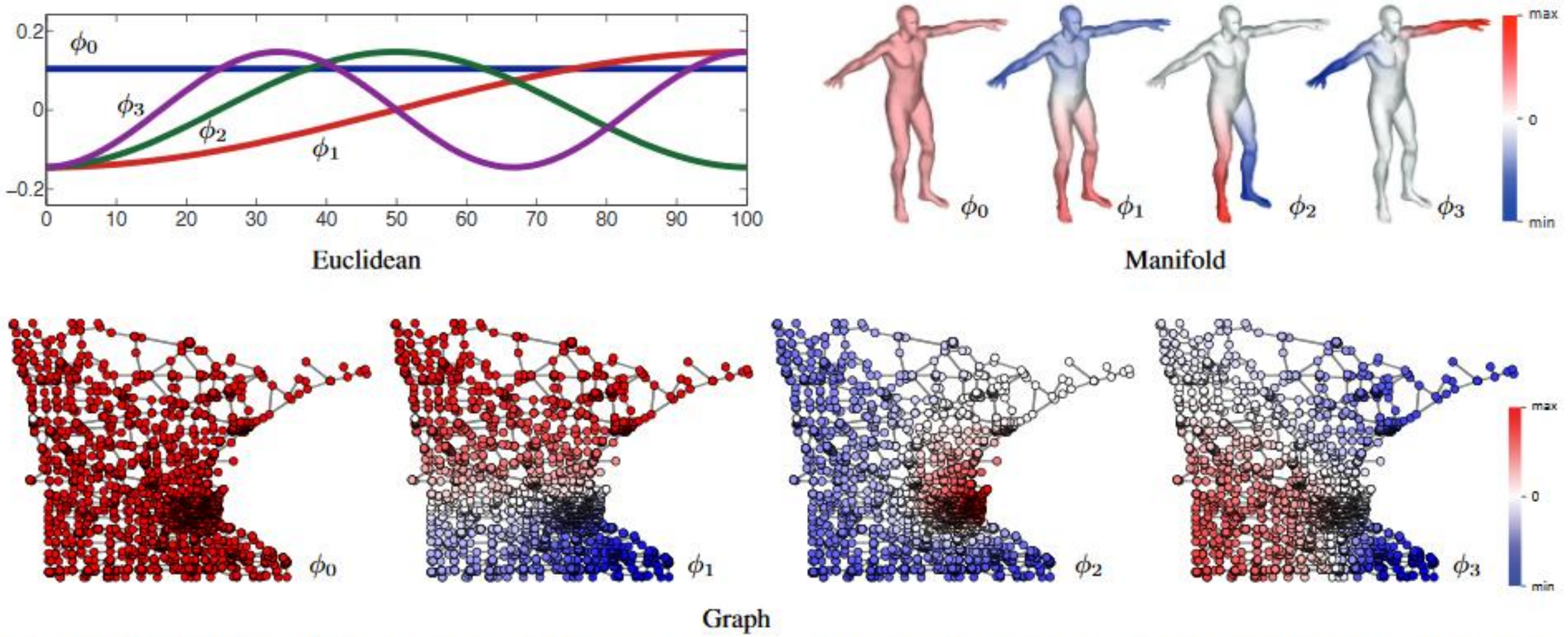



Figure 3.10. Illustration of the quantities used in the derivation of the discrete Laplace-Beltrami operator and discrete Gaussian curvature operator.

Credits to Michael Bronstein et. al., 2016

# Signal approach: Spectral CNN




[FIGS3] Example of the first four Laplacian eigenfunctions $\phi_0, \ldots, \phi_3$ on a Euclidean domain (1D line, top left) and non-Euclidean domains (human shape modeled as a 2D manifold, top right; and Minnesota road graph, bottom). In the Euclidean case, the result is the standard Fourier basis comprising sinusoids of increasing frequency. In all cases, the eigenfunction $\phi_0$ corresponding to zero eigenvalue is constant ('DC').

Credits to Michael Bronstein et. al., 2016

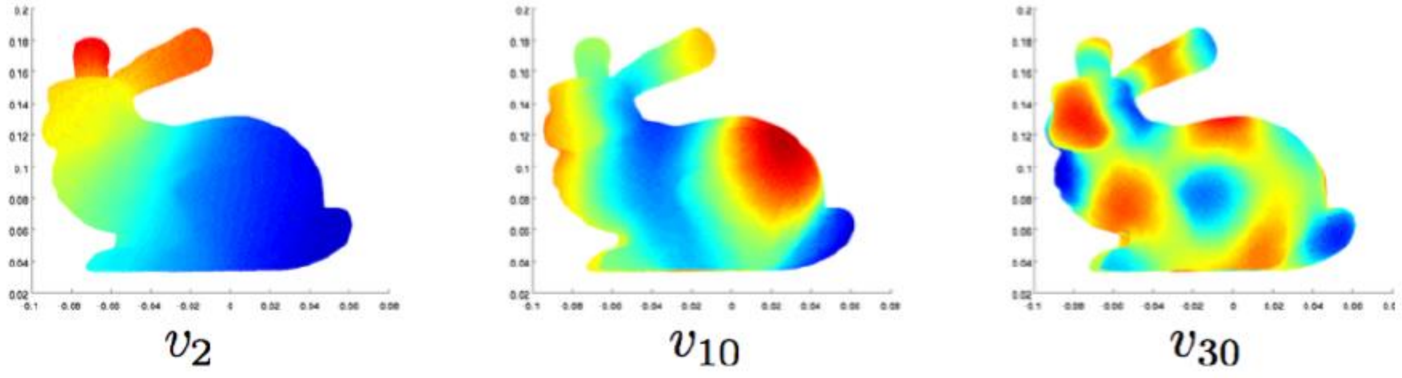
# Signal approach: Spectral CNN

Mesh basis: Eigenfunctions of the Laplace-Beltrami-Operator Δ


Define the filter function g as a function of Laplace-Beltrami-Operator s a Δ

$$g_{\boldsymbol{\alpha}}(\boldsymbol{\Delta}) \quad = \quad \boldsymbol{\Phi} g_{\boldsymbol{\alpha}}(\boldsymbol{\Lambda})\boldsymbol{\Phi}^\top$$ (Eigenspace of Graph)

$$g_{\boldsymbol{\alpha}}(\lambda) = \sum_{j=0}^{r-1} \alpha_j \lambda^j$$ (Function of Eigenvalues)



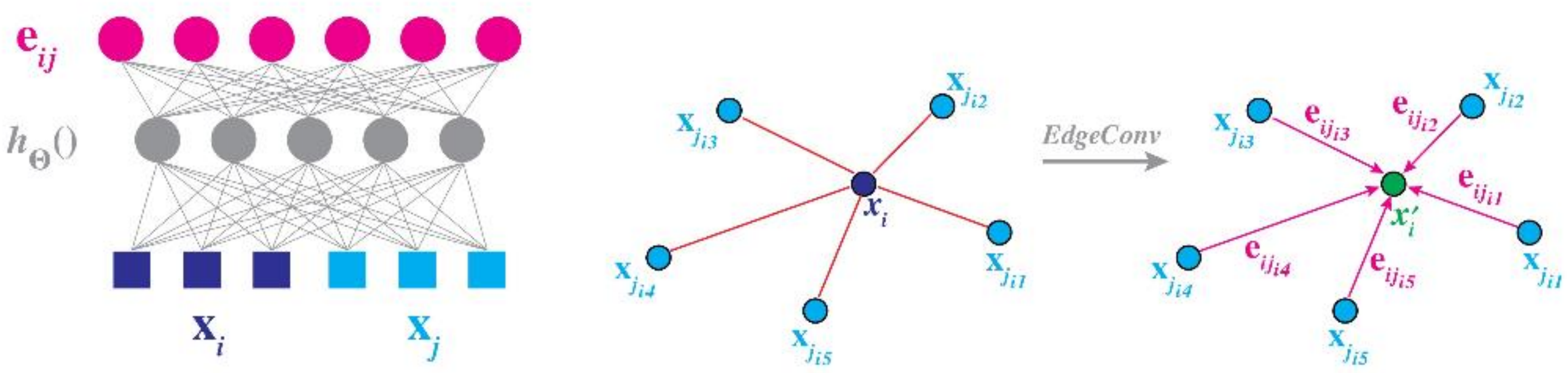

Credits to Mario Botsch et. al., 2010

# Signal approach: Spectral CNN

- Filters are exactly localized in ***r***-hops support
- O(1) parameters per layer
- No computation of ϕ, ϕT ⇒ O(***n***) computational complexity
- Stable under coefficients perturbation
- Filters are basis-dependent ⇒ does not generalize across graphs, i.e. Eigenfunctions are Laplacian-specific and therefore graph specific.

Credits to Jonathan Masci et. al., 2015

# Graph approach: Graph CNN

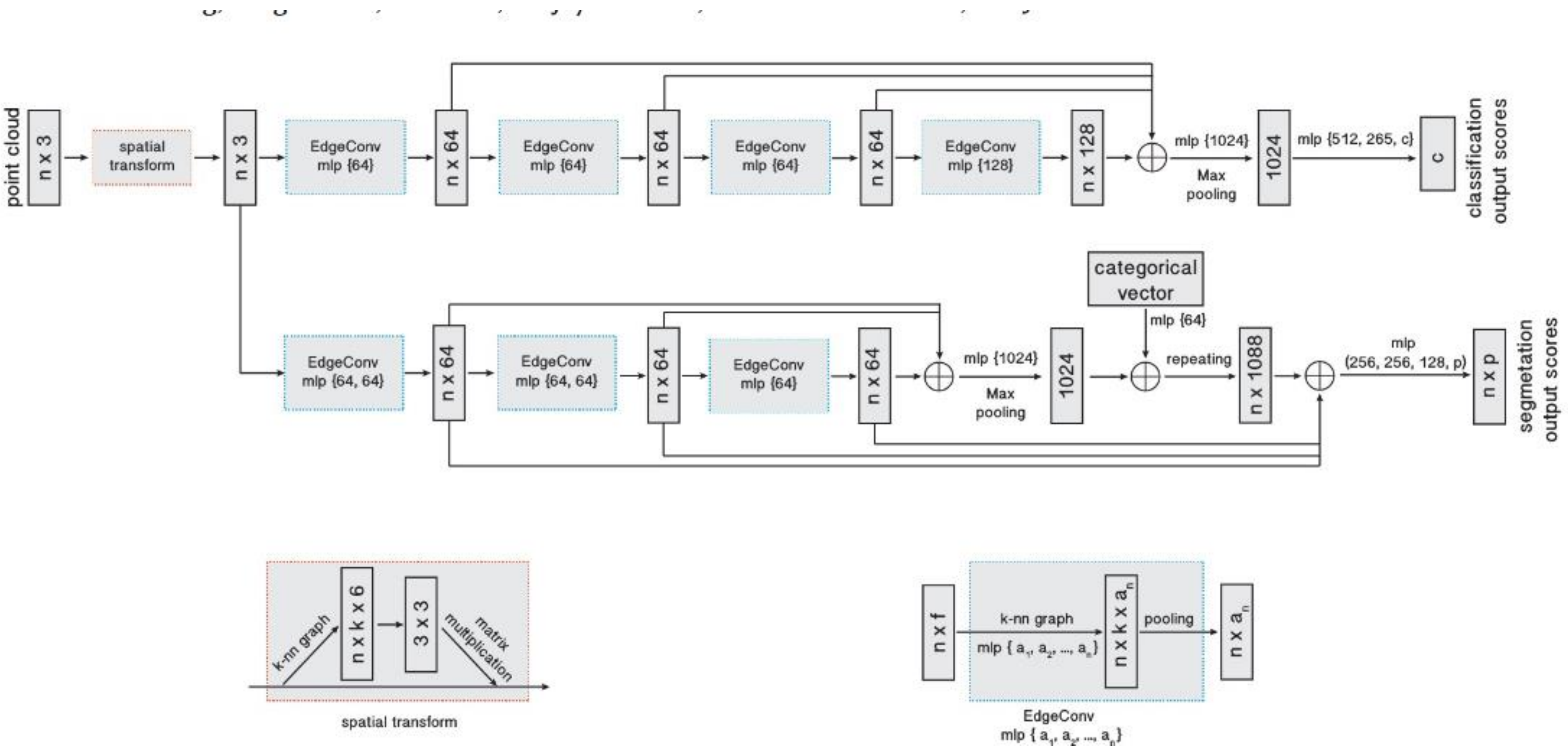



- **Minimal inner** structure (no fixed indexing of the nodes required)
- **Localized** (only neighbors are considered)
- **Weight sharing** (convolution-like operations)
- **Graph topology** independent

$$x_i = f\_gnn(\{x_j : j \rightarrow i\})$$

Credits to Michael Bronstein et. al., 2018

# Graph approach: Graph CNN



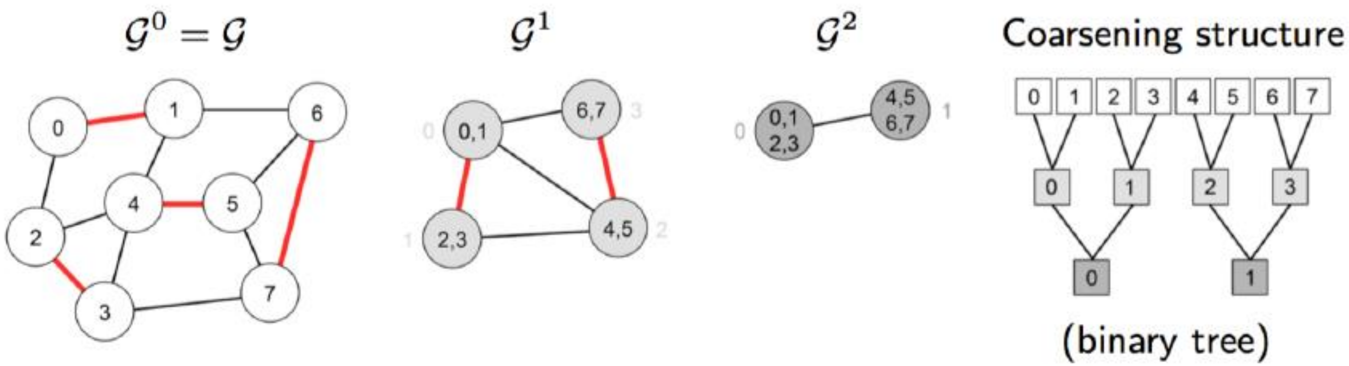

Credits to Michael Bronstein et. al., 2018

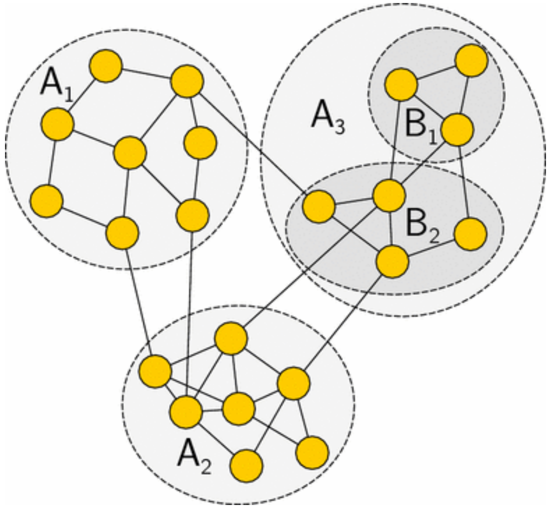
# Graph approach: Graph CNN

- Generalizes well to changing graph topologies
- Unified framework
- Slow k-nearest neighbor searches
- Only pairwise relationships and no assumption about being locally flat

# Graclus, the typical pooling layer

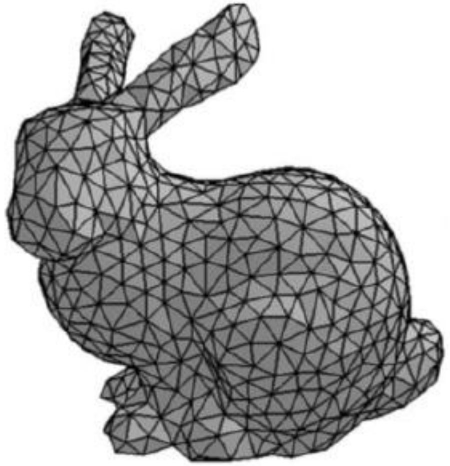
- Graph downsampling == graph coarsening == graph pooling == graph partitioning. Decompose Graph into meaningful clusters.
- Graph partitioning is NP hard → Use Graclus approximation



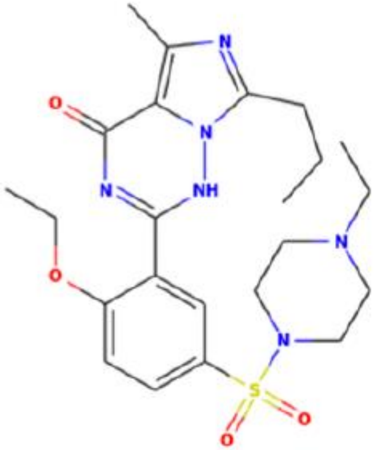

Credits to Dhillon, Guan, Kulis 2007 and Defferrard, Bresson, Vandergheynst 2016

# Techniques can be easily generalized to general graphs



3D shape graph

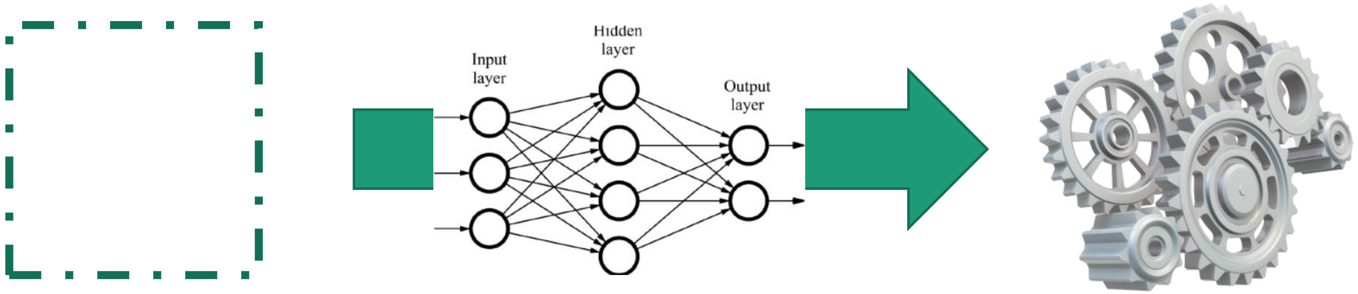
social network




molecules

# Open issues with mesh based representation

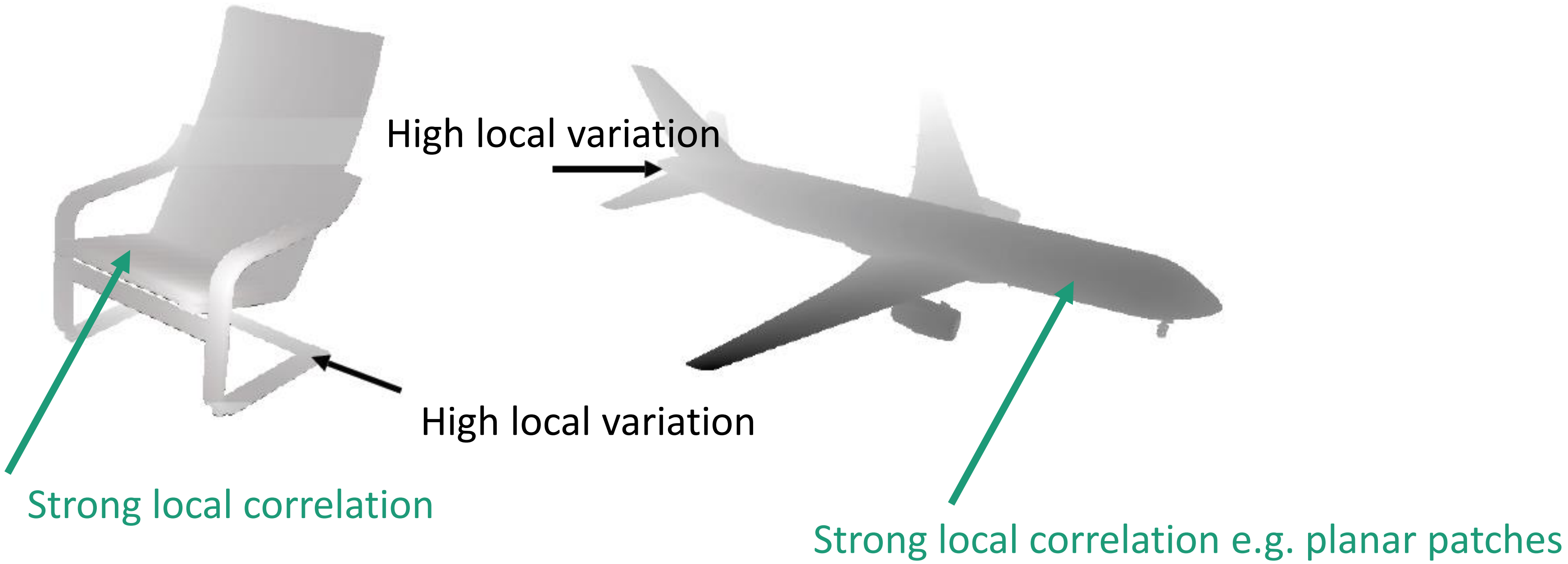
- Mesh as network output is difficult as topology may be variable
- Not clear how to generate shapes with topology variation
- No unique parametrization available, we need to match graphs in order to compute loss function!



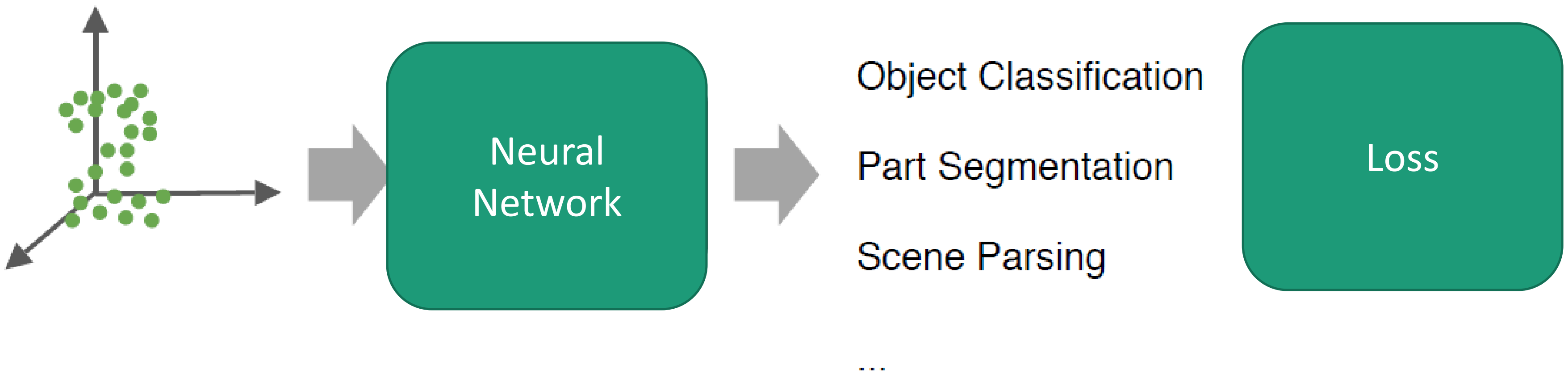
# Deep Learning on point clouds

- *The computer scientists' approach: theory follows implementation –*

# Statistics of geometry



# The desired pipeline

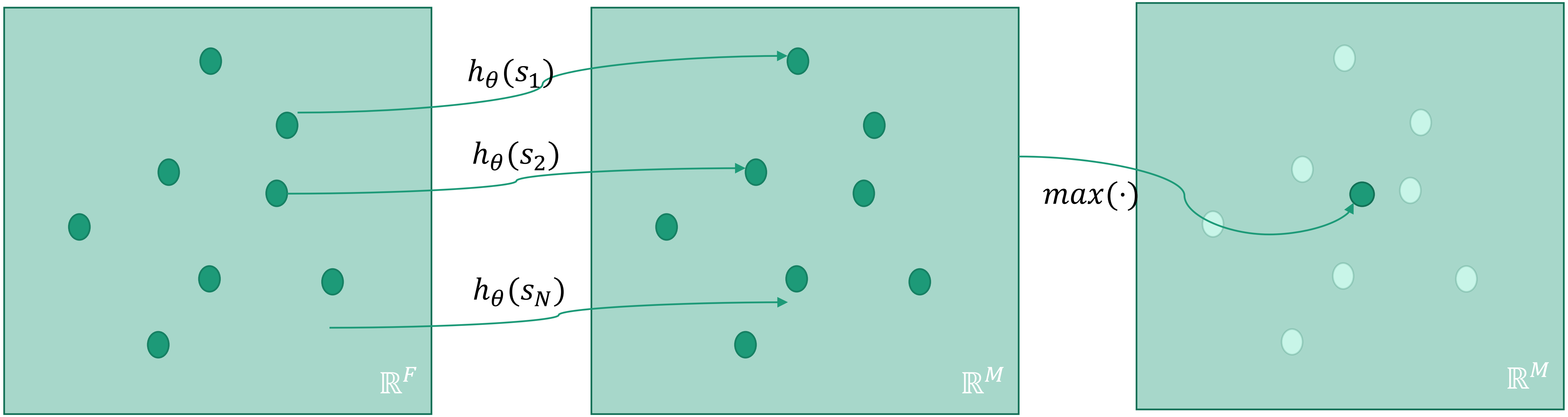



**Natural questions arise:**

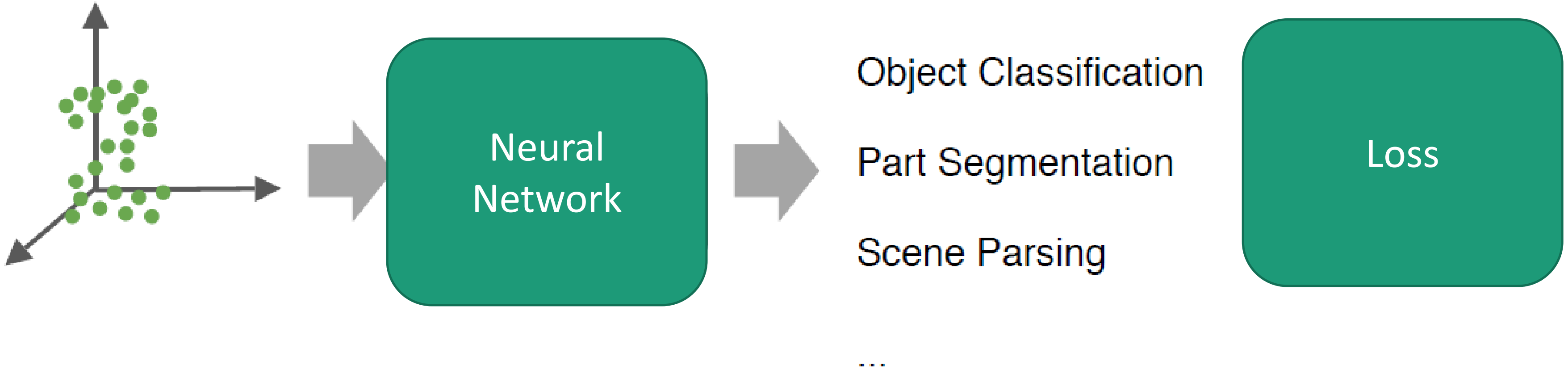
- How to order input points?
- How to induce that nearby points are correlated
- Which loss functions can I use?

# Simple approach

- $f(S) = g(\{h(s_1), h(s_2), \dots, h(s_N)\}),$
  $with\ feature\ map\ h\colon \mathbb{R}^F \rightarrow \mathbb{R}^M, symmetric\ g\colon 2^X \rightarrow \mathbb{R}\ and\ S \supseteq \mathbb{R}^D$



# The desired pipeline



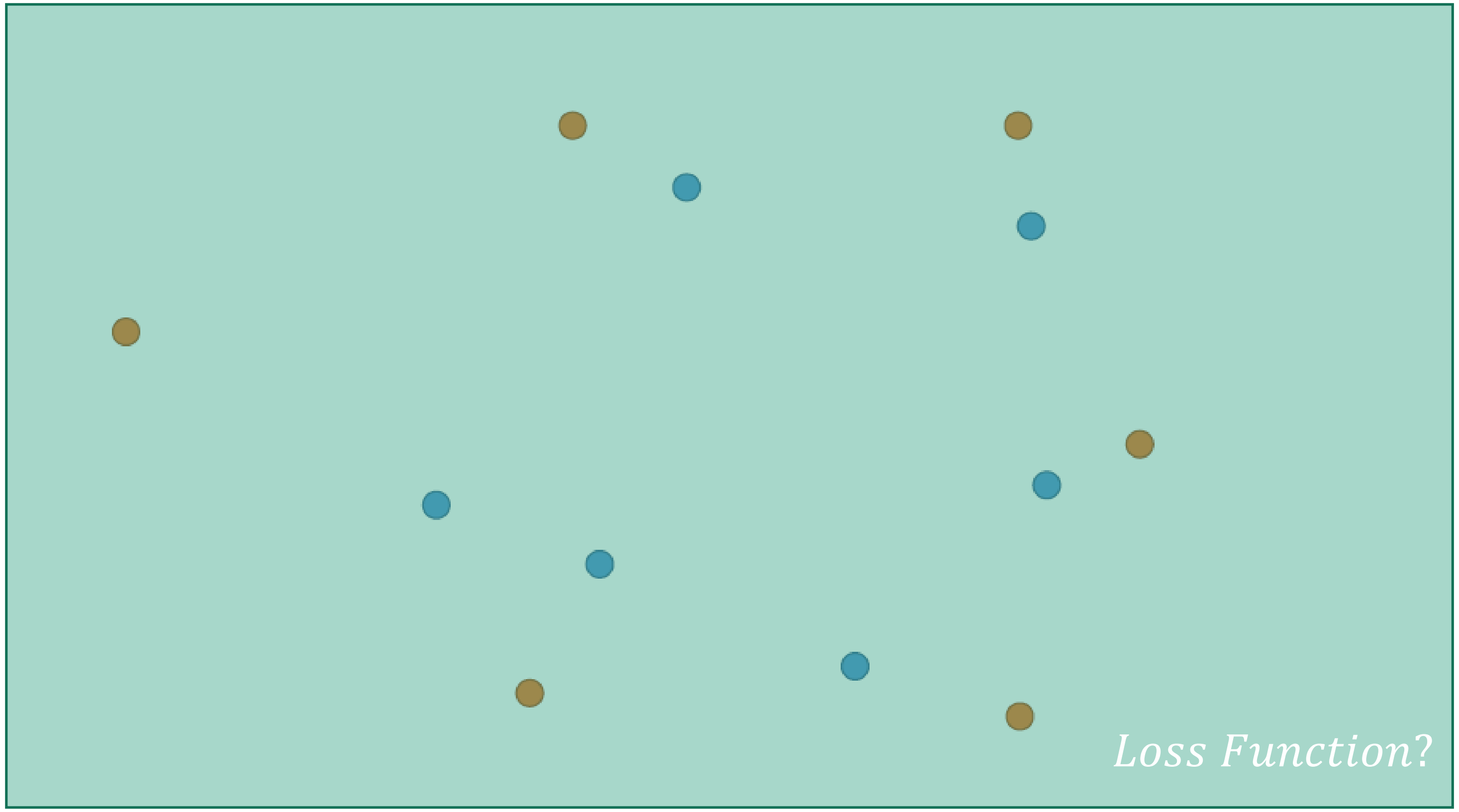

**Natural questions arise:**

- How to order input points? → **Doesn't matter, feature map h() gets applied individually**
- How to induce that nearby points are correlated → **Learned from data**
- Which loss functions can I use? → **g() yields a vector, standard losses for classification, etc.**

→ What about segmentation, deconvolution, predicting points?

# Example semantic segmentation

# Correspondence problem when predicting point clouds

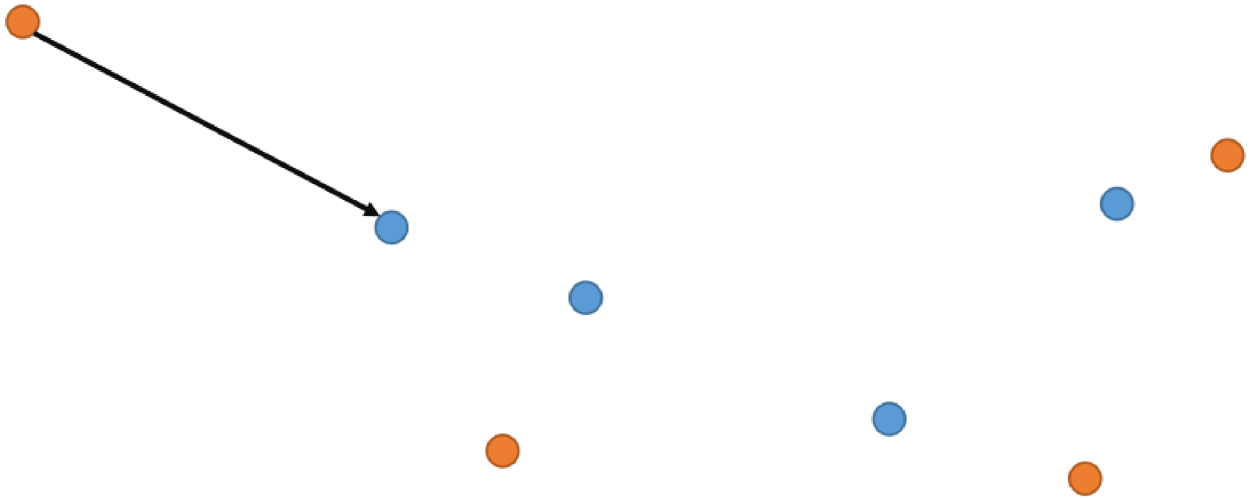



Given two sets of points, measure their discrepancy

# Typical distances between sets

$$d_{Hausdorff}(S_1, S_2) = \max_{x \in S_1} \min_{y \in S_2} ||x - y||_2^2 + \max_{x \in S_2} \min_{y \in S_1} ||x - y||_2^2$$

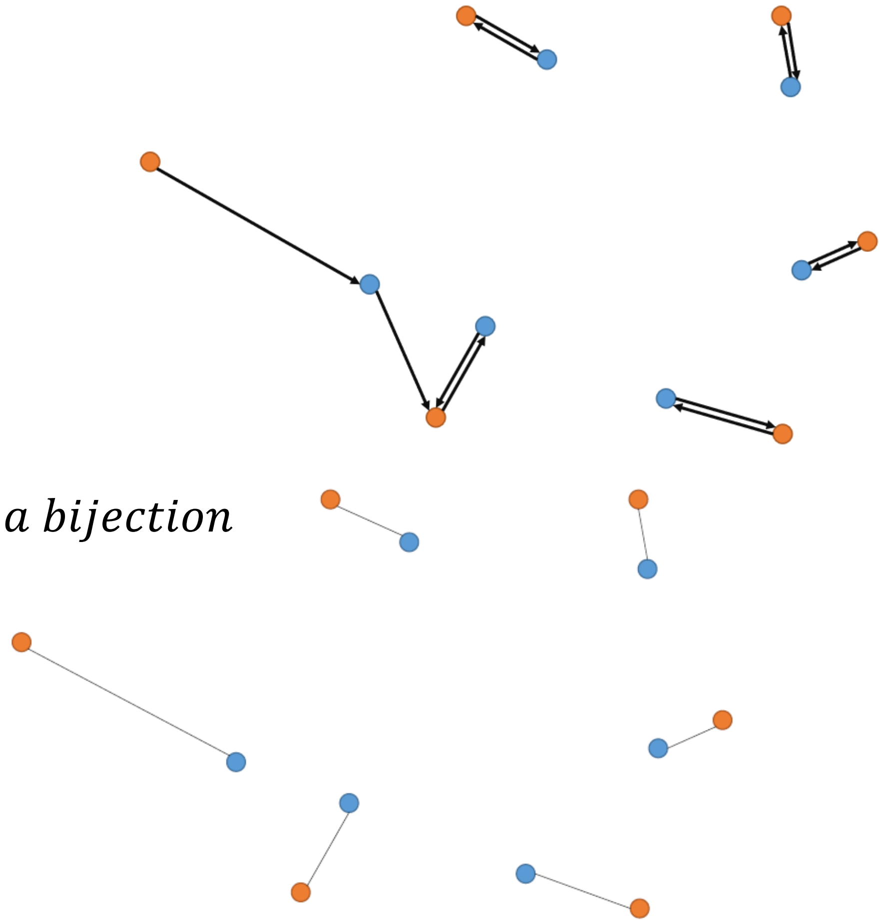
**Not very robust!**



# Typical distances between sets

$$d_{Chemfer}(S_1, S_2) = \sum_{x \in S_1} \min_{y \in S_2} ||x-y||_2^2 + \sum_{x \in S_2} \min_{y \in S_1} ||x-y||_2^2$$

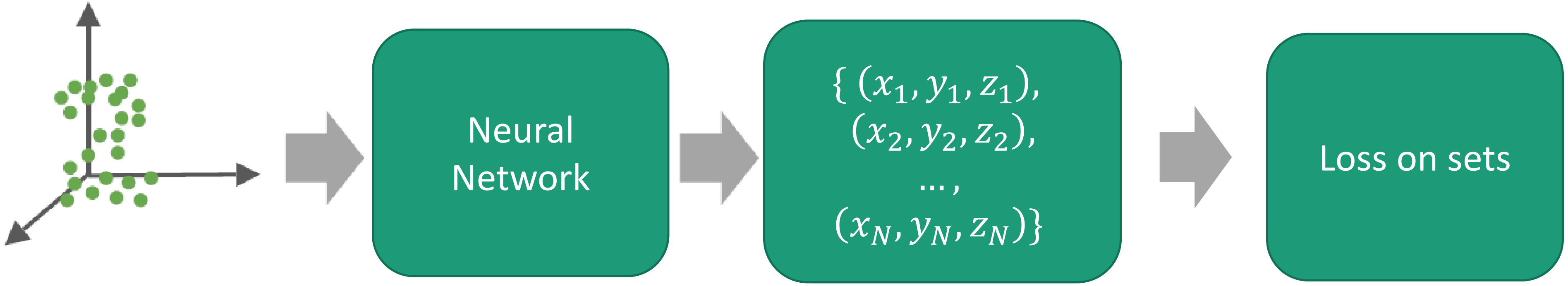
$$d_{EarthMover}(S_1, S_2) = \min_{\phi : x_1 \to x_2} \sum_{x \in S_1} ||x-\phi(x)||_2^2 \text{ } with\ \phi : S_1 \to S_2\ is\ a\ bijection$$



Simple function of coordinates:

- In general positions, the correspondence is unique
- With infinitesimal movement, the correspondence does not change
- **Conclusion: differentiable almost everywhere**

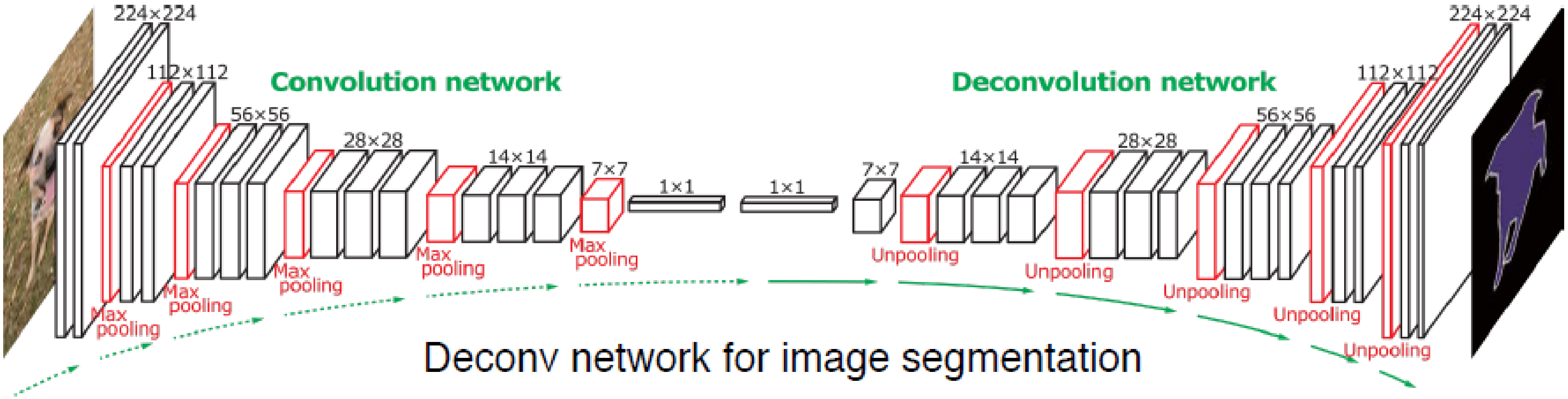
# The desired pipeline for point predictions




…

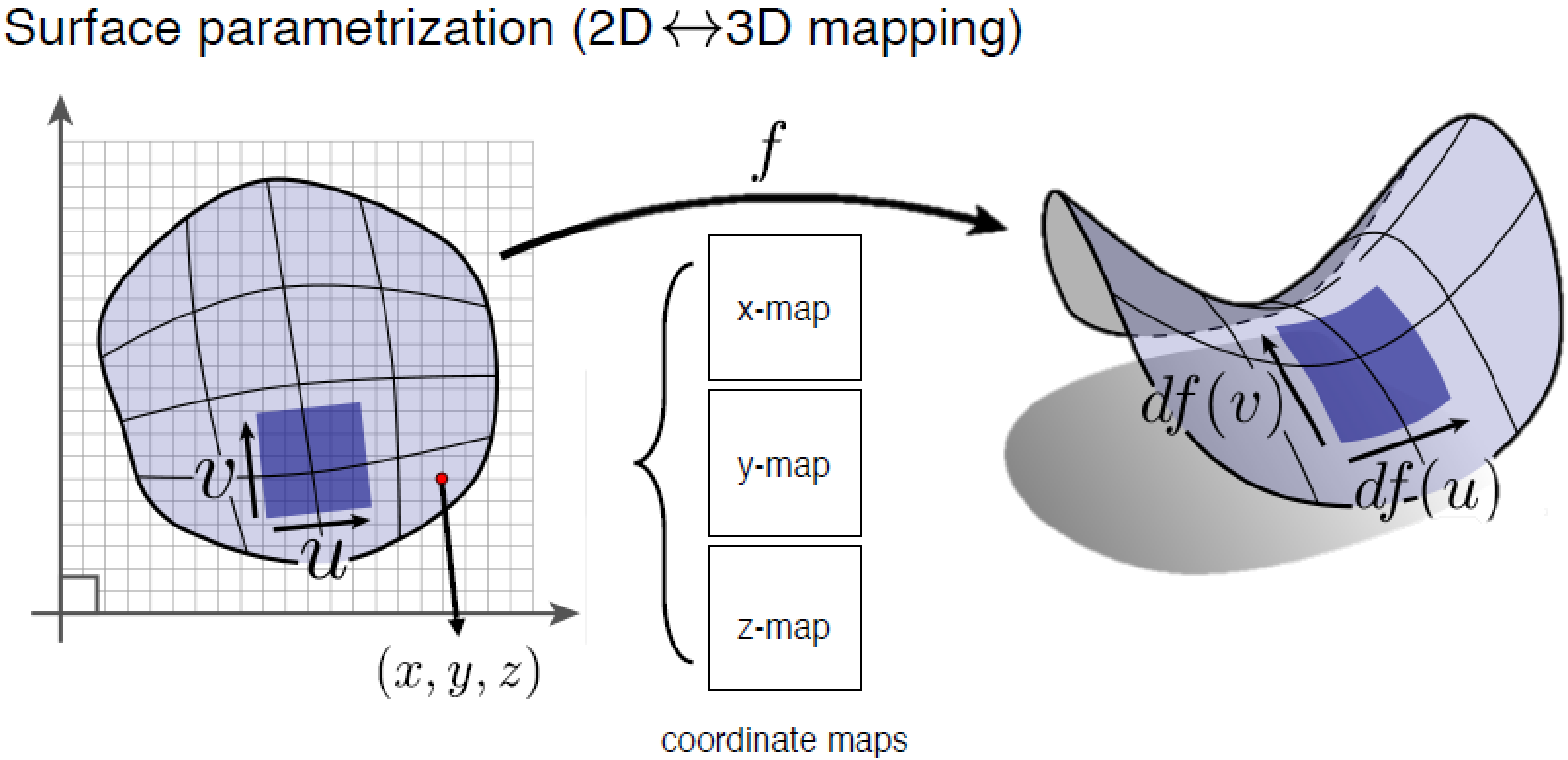
→ We want to predict points in space! How to implement devonvolution?

# Recap Image Segmentation with DeconvNet



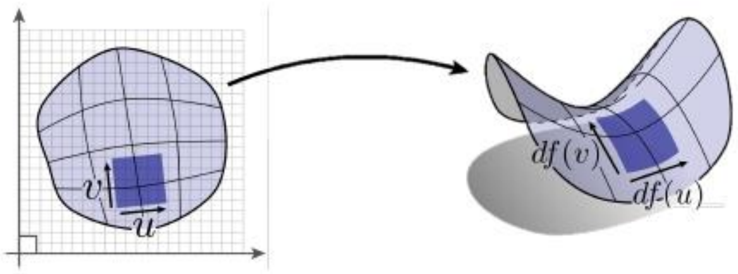

Credit: FCNN, Long et al.

# Observation: Parametrization looks like image deconvolution

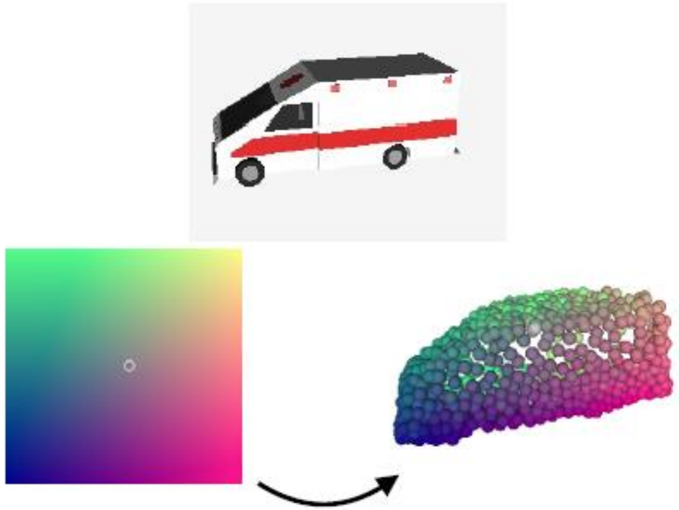


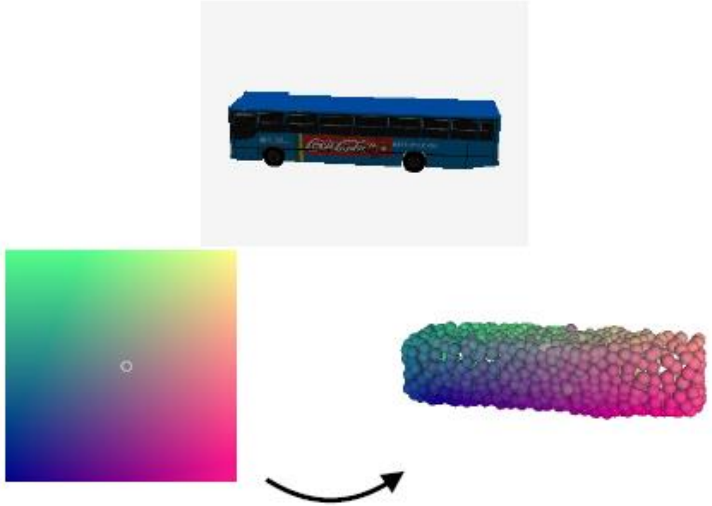

Credits Keenan Crane, 2019

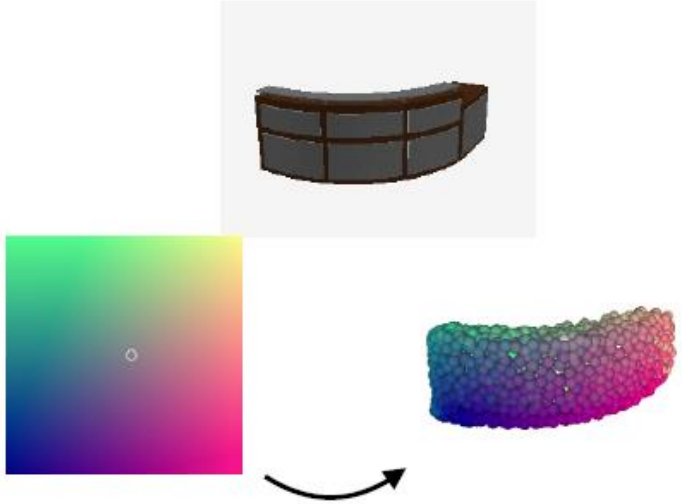
# Example Smooth Point Cloud Prediction



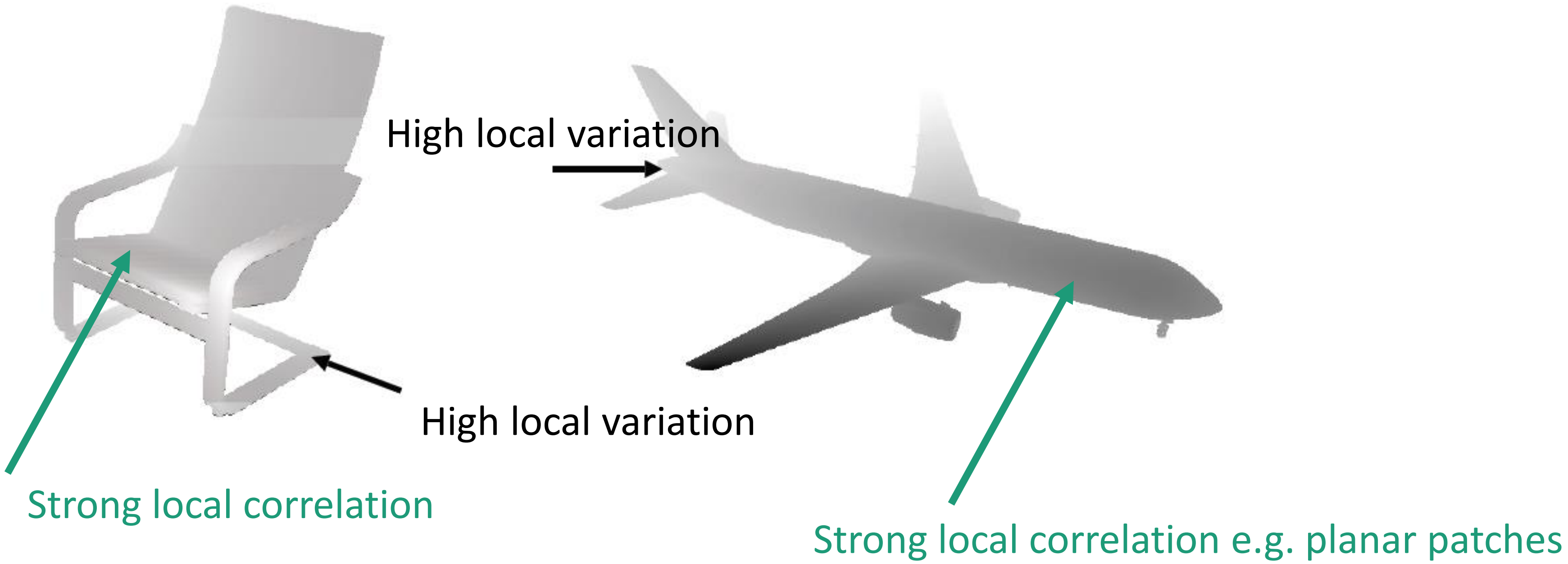

**Network outputs are coordinate maps (x, y, z) !**



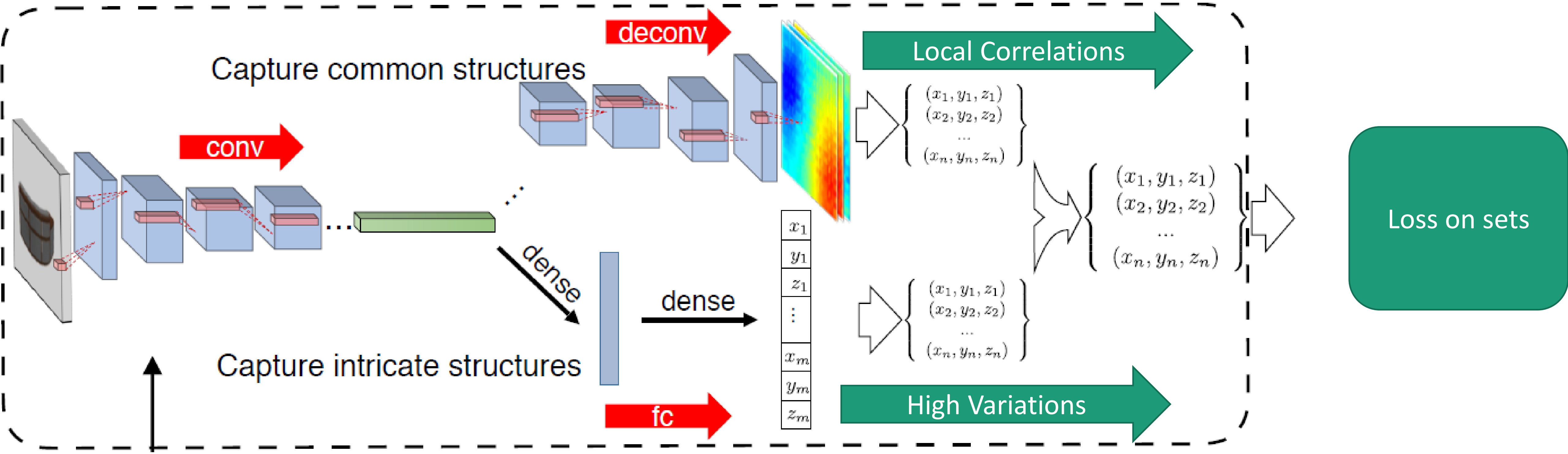




# Recap: Statistics of geometry



# Full example architecture of a point network

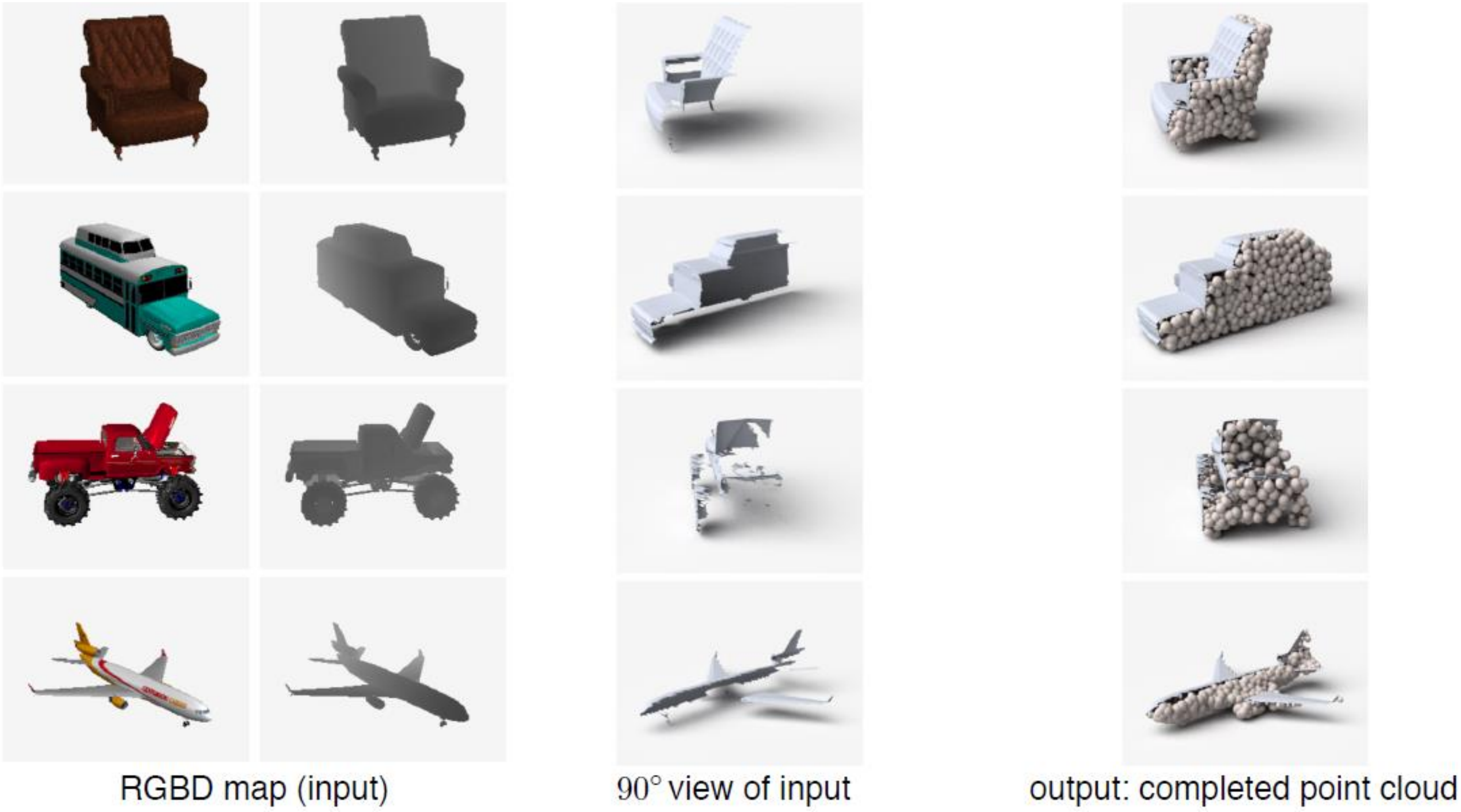



Credit Hao Su, 2017

# Sharp and Smooth structures

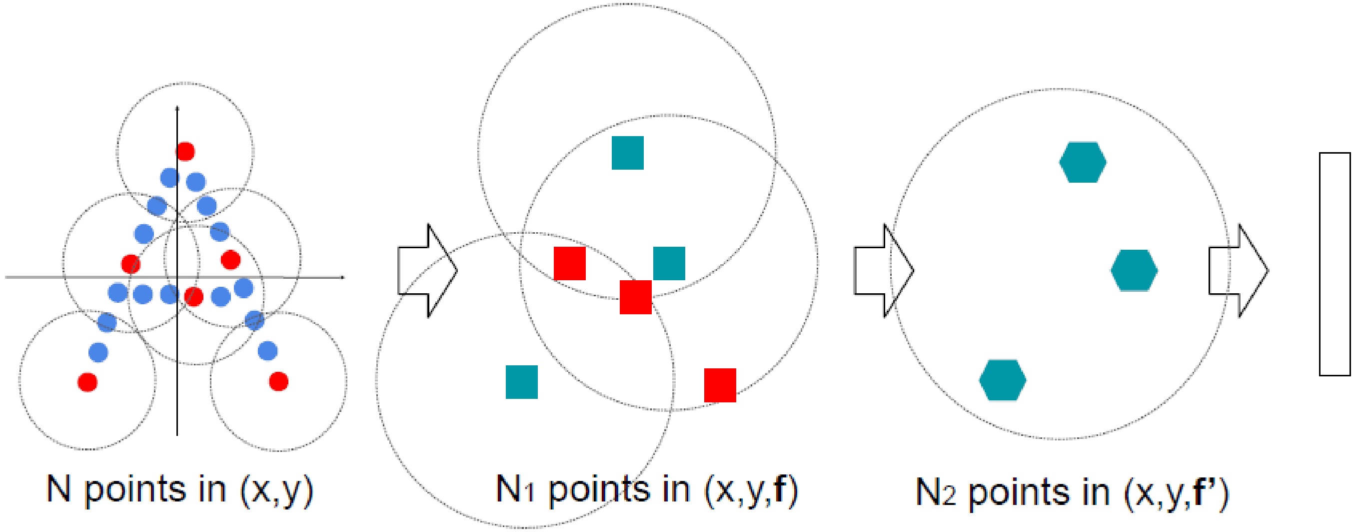
CVPR '17, Point Set Generation

# Example Shape Completion from RGB-D




Credit Hao Su, 2017

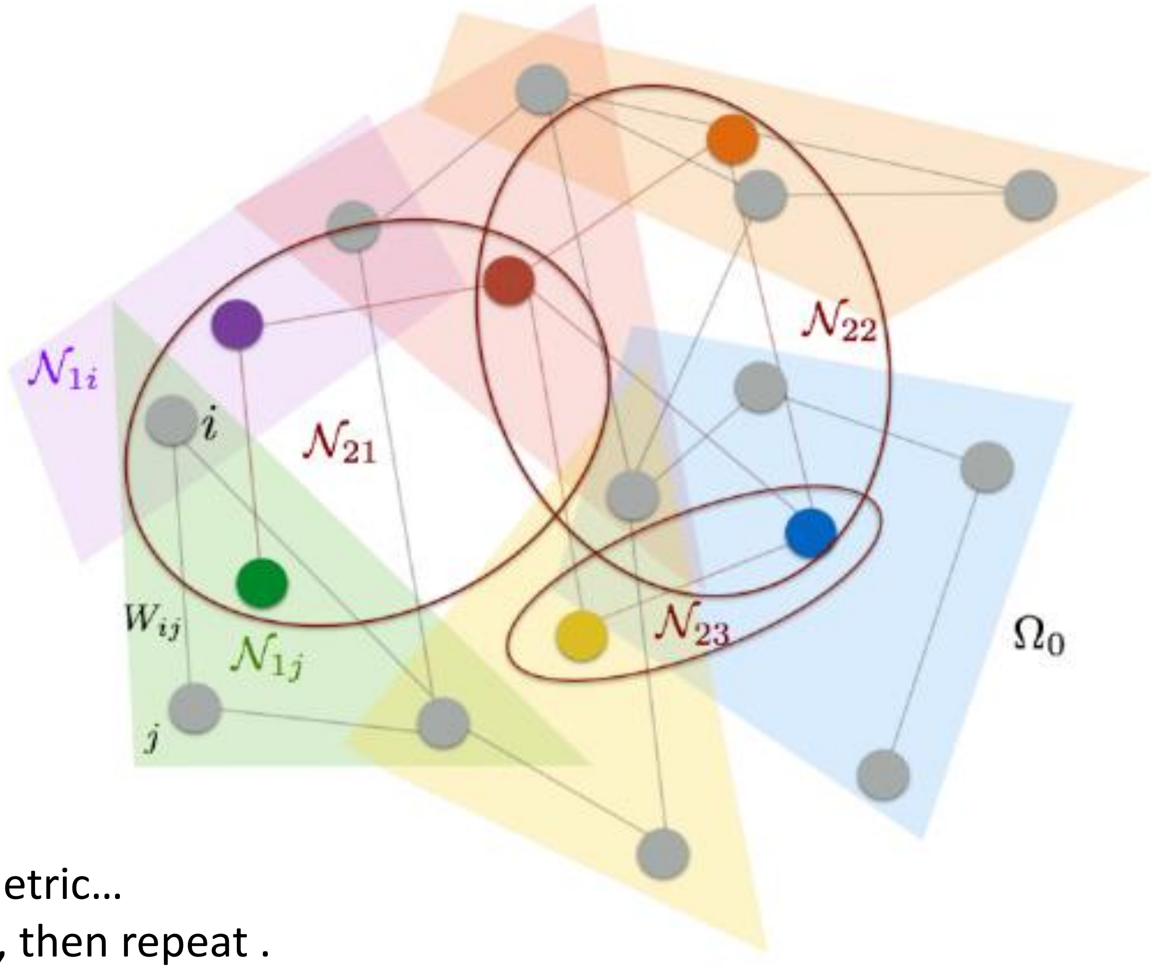
# Farthest point sampling (FPS), the typical pooling layer



# Common Framework

- *Everything is a graph -*

# Comparing to Graph CNN



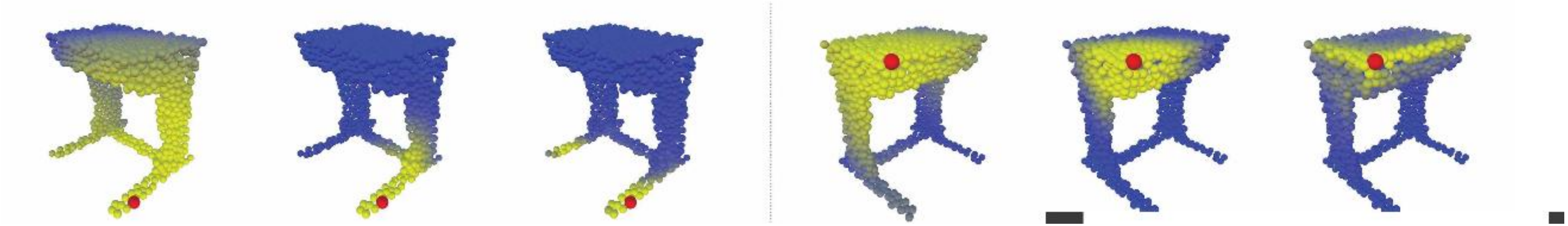

Very similar to Graph CNN with euclidean metric…
…Local feature extraction, graph coarsening, then repeat .

Joan Bruna et. al., 2014

# Graph CNN as a unification framework

| | Aggregation | Edge Function | Learnable parameters |
|---|---|---|---|
| PointNet [Qi et al. 2017b] | – | $h_\Theta(\mathbf{x}_i, \mathbf{x}_j) = h_\Theta(\mathbf{x}_i)$ | $\Theta$ |
| PointNet++ [Qi et al. 2017c] | max | $h_\Theta(\mathbf{x}_i, \mathbf{x}_j) = h_\Theta(\mathbf{x}_j)$ | $\Theta$ |
| MoNet [Monti et al. 2017a] | $\sum$ | $h_{\theta_m, w_n}(\mathbf{x}_i, \mathbf{x}_j) = \theta_m \cdot (\mathbf{x}_j \odot g_{w_n}(u(\mathbf{x}_i, \mathbf{x}_j)))$ | $w_n, \theta_m$ |
| PCNN [Atzmon et al. 2018] | $\sum$ | $h_{\theta_m}(\mathbf{x}_i, \mathbf{x}_j) = (\theta_m \cdot \mathbf{x}_j) g(u(\mathbf{x}_i, \mathbf{x}_j))$ | $\theta_m$ |

Table 1. Comparison to existing methods. The per-point weight $w_i$ in [Atzmon et al. 2018] effectively is computed in the first layer and could be carried onward as an extra feature; we omit this for simplicity.



Credits to Michael Bronstein et. al., 2018

# Example in PyTorch

```
class Net(torch.nn.Module):
    def __init__(self):
        super(Net, self).__init__()

        nn = Seq(Lin(coord_dims, 64), ReLU(), Lin(64, 64))
        self.conv1 = PointConv(local_nn=nn)

        nn = Seq(Lin(coord_dims + 64, 128), ReLU(), Lin(128, 128))
        self.conv2 = PointConv(local_nn=nn)

        self.lin2 = Lin(128, 256)
        self.lin3 = Lin(256, num_classes)

    def forward(self, data):
        pos, batch = data.pos, data.batch

        edge_index = radius_graph(pos, r=0.2, batch=batch)
        x = F.relu(self.conv1(None, pos, edge_index))

        idx = fps(pos, batch, ratio=0.5)
        x, pos, batch = x[idx], pos[idx], batch[idx]

        edge_index = radius_graph(pos, r=0.2, batch=batch)
        x = F.relu(self.conv2(x, pos, edge_index))
        x = global_max_pool(x, batch)
        x = F.relu(self.lin2(x))
        x = self.lin3(x)
        return F.log_softmax(x, dim=-1)

model = Net()
optimizer = torch.optim.SGD(model.parameters(), lr=lrate, momentum=0.95)
loss = (lambda x, y: F.nll_loss(F.log_softmax(x, dim=1), y))

from ummon import *
with Logger(loglevel=20, logdir='', log_batch_interval=1) as lg:
    trn = ClassificationTrainer(lg, model, loss, optimizer)
    trn.fit(train_loader, epochs=100)
```

# Graph CNN

- Practical applicable, easy to understand, fast, works well
- Unified framework, easy to implement
- Models only pairwise correlations
- Not using curvature information
- Set theoretic approach
- Not Riemannian

**Theorem:**

A Hausdorff continuous symmetric function $f : 2^{\mathcal{X}} \to \mathbb{R}$ can be arbitrarily approximated by PointNet.

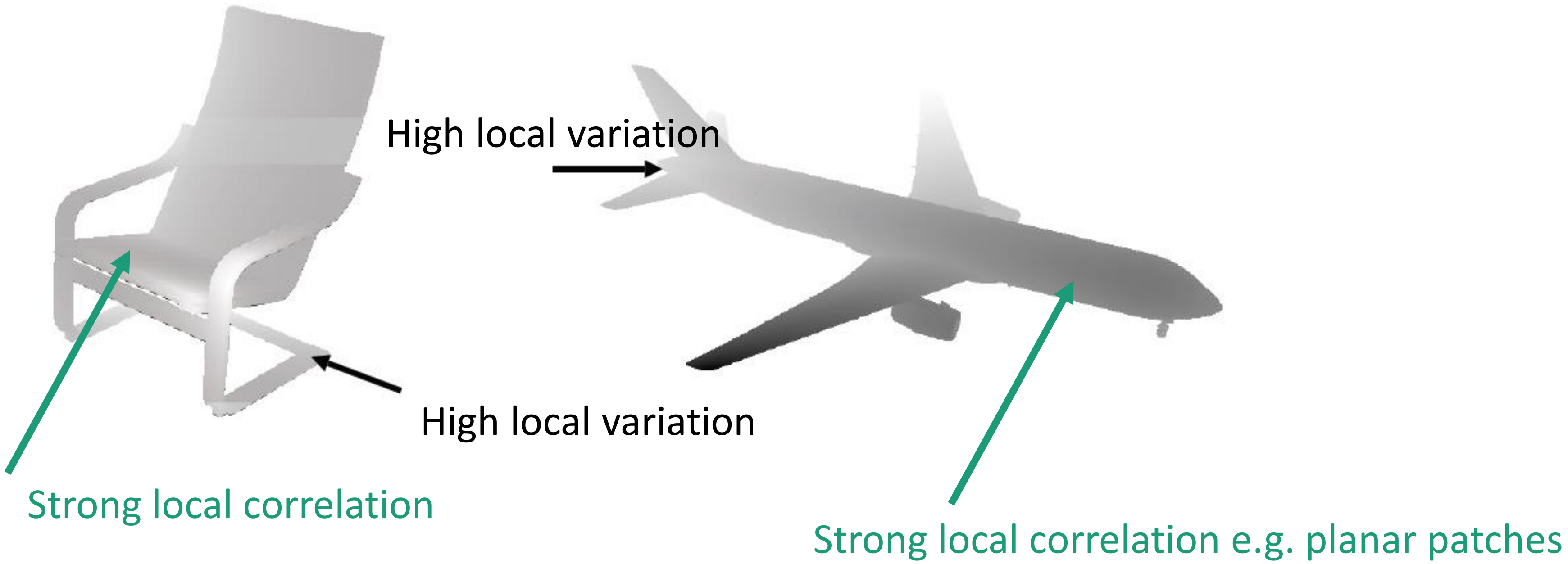
$$\left| f(S) - \underbrace{\gamma\left(\underset{x_i \in S}{\mathrm{MAX}}\{h(x_i)\}\right)}_{\text{PointNet (vanilla)}} \right| < \epsilon$$

$S \subseteq \mathbb{R}^d$,

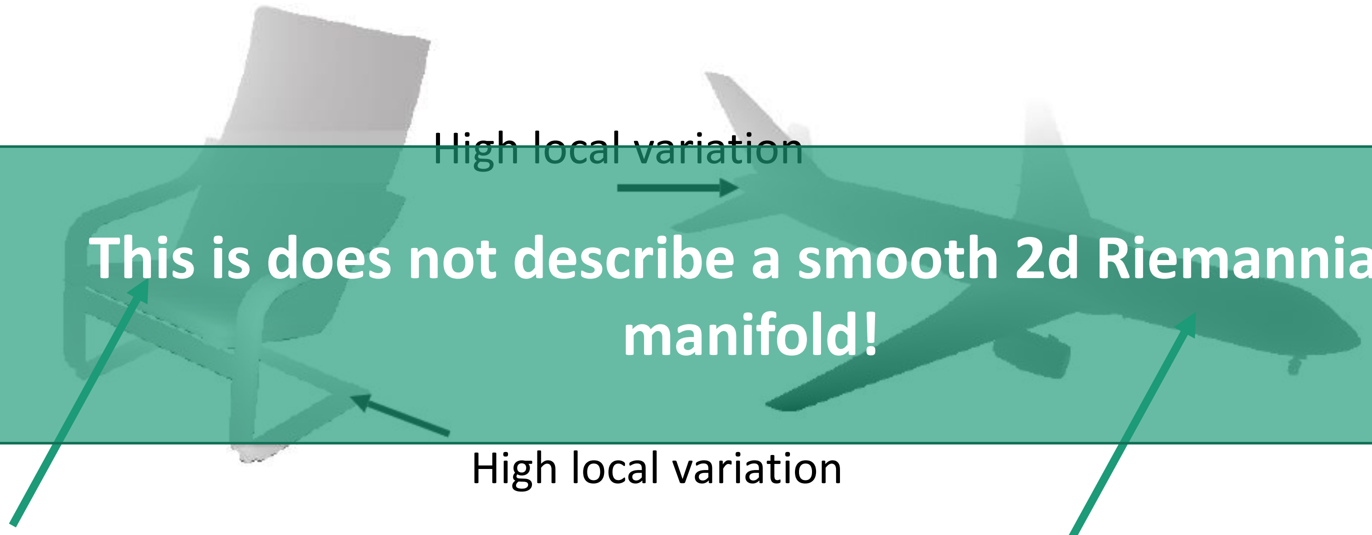
# Cool, but only half the story!

- *Carl Friedrich says-*

# Recap: Statistics of geometry

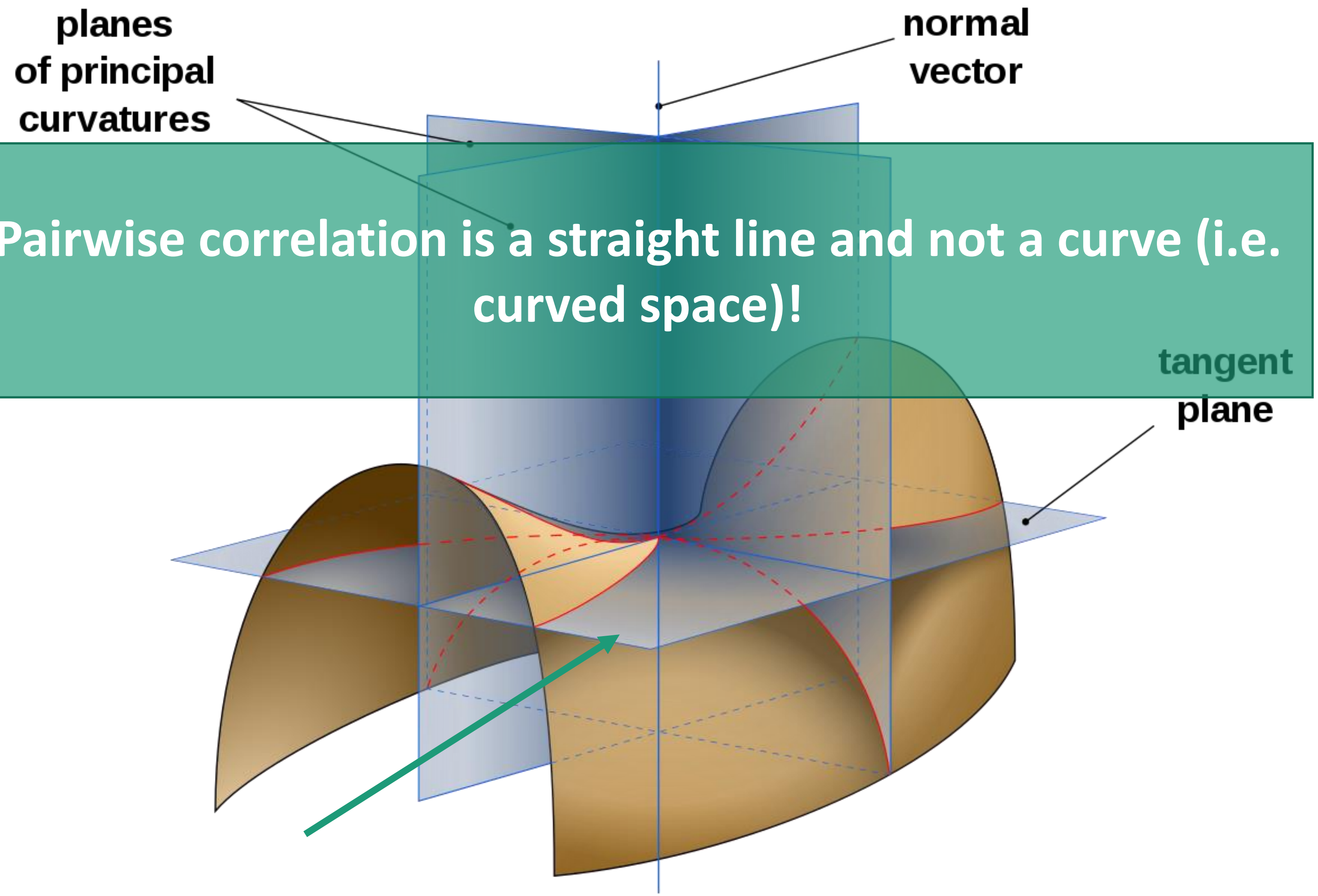


# Recap: Statistics of geometry




**This is does not describe a smooth 2d Riemannian manifold!**

# Why is it not a 2d Riemannian manifold?




**Pairwise correlation is a straight line and not a curve (i.e. curved space)!**

# And, topological algebra does Deep Learning, too

## Gauge Equivariant Convolutional Networks and the Icosahedral CNN

Taco S. Cohen [*1] Maurice Weiler [*2] Berkay Kicanaoglu [*2] Max Welling [1]

**Current Graph CNNs only work for scalar functions, what about wind directions?**



**Abstract**

The principle of *equivariance to symmetry transformations* enables a theoretically grounded approach to neural network architecture design. Equivariant networks have shown excellent performance and data efficiency on vision and medical imaging problems that exhibit symmetries. Here we show how this principle can be extended beyond global symmetries to local gauge transformations. This enables the development of a very general class of convolutional neural networks on manifolds that depend only on the intrinsic geometry, and which includes many popular methods from equivariant and geometric deep learning.

We implement gauge equivariant CNNs for sig-

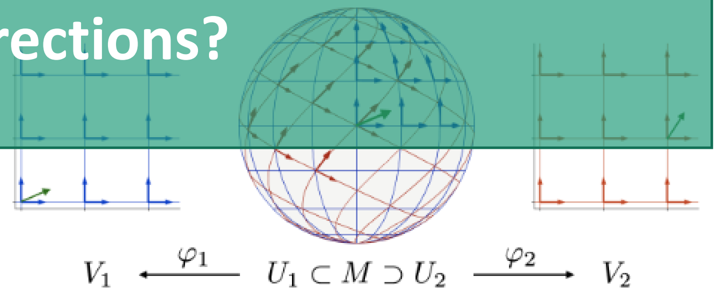
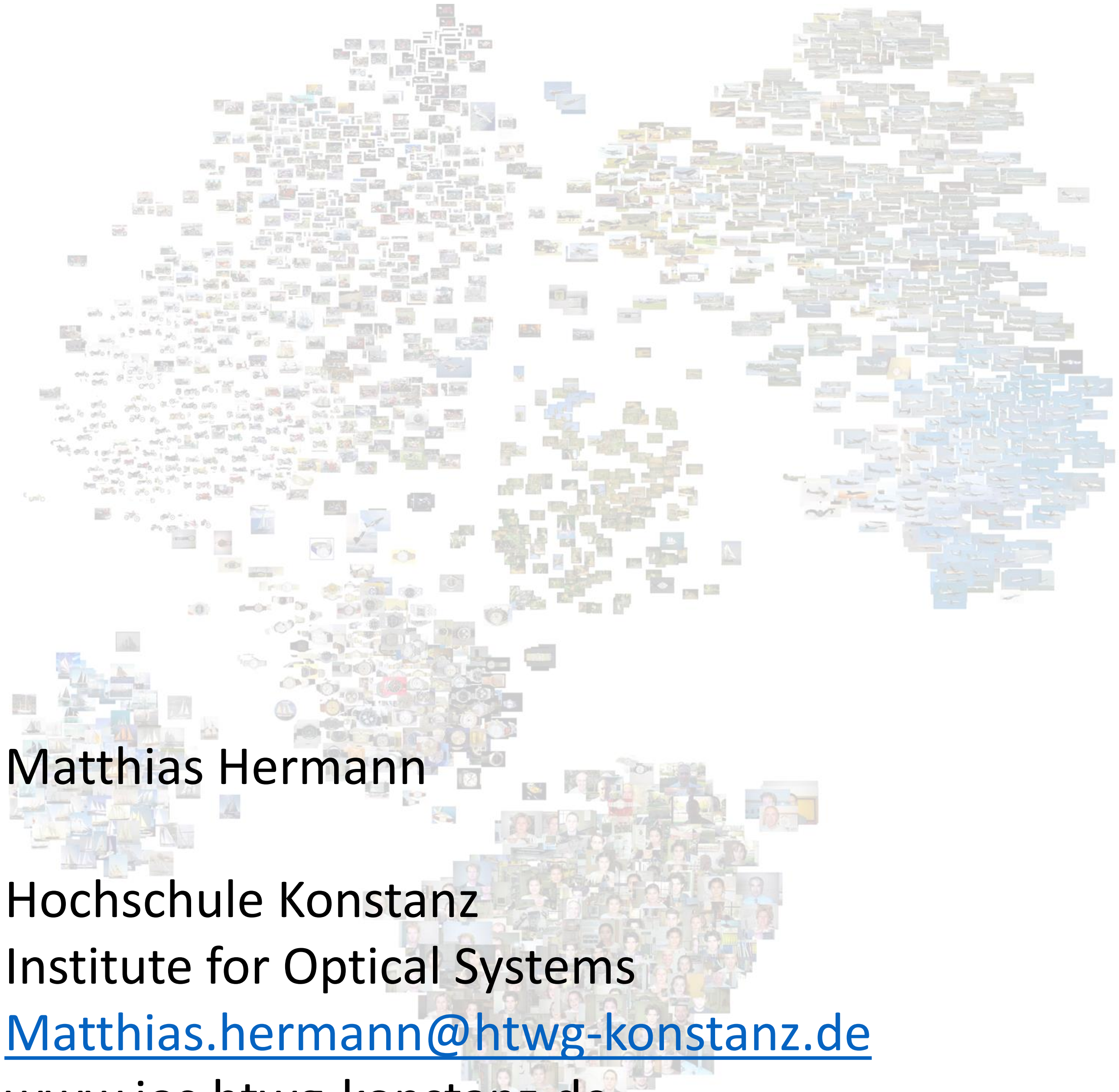



*Figure 1.* A gauge is a smoothly varying choice of tangent frame on a subset $U$ of a manifold $M$. A gauge is needed to represent geometrical quantities such as convolutional filters and feature maps (i.e. fields), but the choice of gauge is ultimately arbitrary. Hence, the network should be equivariant to gauge transformations, such as the change between red and blue gauge pictured here.

# Thanks for your attention!



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# Literature


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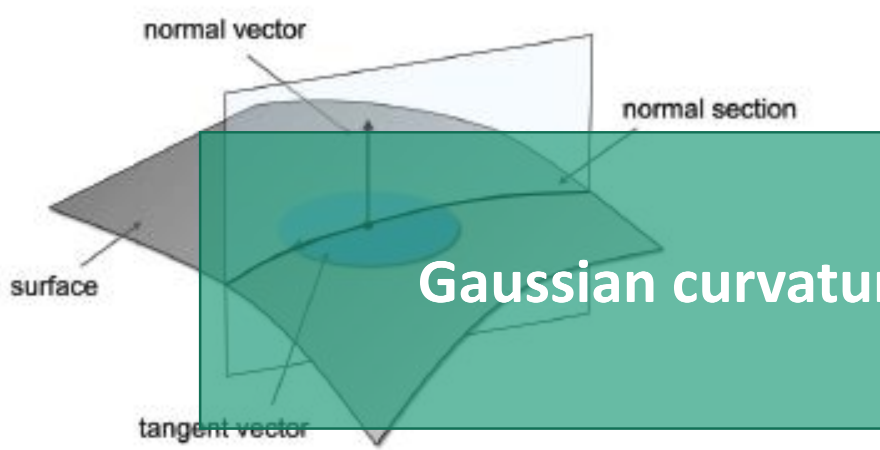
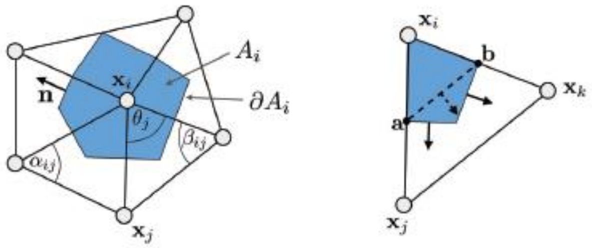
# Next time, integrating curvature!





**Gaussian curvature is an intrinsic property!**

$$\Delta f = div\nabla f = f_{uu} + f_{vv}$$

$$K = \frac{< (\nabla_{e2}\nabla_{e1} - \nabla_{e1}\nabla_{e2})e_1, e_2 >}{\det g}$$