AutoAssign: Differentiable Label Assignment for Dense Object Detection

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Abstract

In this paper, we propose an anchor-free object detector with a fully differentiable label assignment strategy, named AutoAssign. It automatically determines positive/negative samples by generating positive and negative weight maps to modify each location’s prediction dynamically. Specifically, we present a center weighting module to adjust the category-specific prior distributions and a confidence weighting module to adapt the specific assign strategy of each instance. The entire label assignment process is differentiable and requires no additional modification to transfer to different datasets and tasks. Extensive experiments on MS COCO show that our method steadily surpasses other best sampling strategies by \(\sim 1\%\) AP with various backbones. Moreover, our best model achieves 52.1% AP, outperforming all existing one-stage detectors. Besides, experiments on other datasets, e.g., PASCAL VOC, Objects365, and WiderFace, demonstrate the broad applicability of AutoAssign.

1. Introduction

Current state-of-the-art CNN based object detectors perform a common paradigm of dense prediction. Both two-stage (the RPN [17] part) and one-stage detectors [11, 20, 27, 26] predict objects with various scales, aspect ratios, and classes over every CNN feature locations in a regular, dense sampling manner.

This dense detection task raises an essential issue of sampling positives and negatives in the spatial locations, which we call label assignment. Moreover, as the modern CNN-based detectors commonly adopt multi-scale features (e.g., FPN [10]) to alleviate scale variance, label assignment requires not only selecting locations among spatial feature maps but also choosing the level of features with appropriate scale.

As shown in Fig. 1, existing detectors mainly sample the positive and negative locations by human prior: (1) Anchor-based detectors like RetinaNet [11] preset several anchors of diverse scales and aspect ratios on each location and re-sort to the Intersection over Union (IoU) for sampling positives and negatives among spatial and scale-level feature maps. (2) Anchor-free detectors like FCOS [20] sample a fixed fraction of center area as spatial positive locations for each object, and select certain stages of FPN [10] by the pre-defined scale constraints. These detectors follow the prior distribution of the objects to design their assignment strategies, which are proved to be effective on challenging benchmarks, e.g., Pascal VOC [3, 4] and MS COCO [12].

However, as shown in Fig. 2 in the real world, appearances of objects vary a lot across categories and scenarios. The fixed center sampling strategy may pick locations outside objects as positives. Intuitively, sampling locations on objects is better than the plain background because these locations are prone to generate higher classification confidences. On the other hand, although CNN can learn offsets, the obstacle caused by feature shifting when backgrounds are sampled as positives may decrease the performance.

Thus the fixed strategies above may not always select the most appropriate locations among spatial and scale dimensions. Beyond the pure human-designed strategies, a few recent works introduce some partially data-dependent and dynamic strategies in label assignment. GuidedAnchoring [21] and MetaAnchor [23] dynamically change the prior of anchor shapes before sampling, while other methods adaptively modify the sampling strategy for each object in the spatial dimension [27, 26, 9] or the scale dimension [31]. These strategies only free a part of label assignment to be
Figure 2. Comparison of label assignment between FCOS and AutoAssign. Label assignment results of FCOS are fixed, while AutoAssign makes label assignment results to be dynamic data-driven, while the other parts stay constrained by human designs, preventing label assignment from being further optimized.

In this work, we propose a fully differentiable strategy for label assignment. As illustrated in Fig. 1 we first follow the anchor-free manner like FCOS [20] to directly predict objects on each locations without human-designed anchors. In order to retain enough locations for further optimizing, we initially treat all the locations inside a bounding box as both positive and negative candidates at all scale levels. Then we generate positive and negative weight maps to modify the prediction in the training loss. To accommodate the distribution from different categories and domains, we propose a category-wise weighting module named center weighting to learn the distribution of each category from data. To get adapted to the appearance and scale of each instance, we propose a confidence weighting module to modify the positive and negative confidences of the locations in both spatial and scale dimensions. Then we combine the two modules to generate positive and negative weight maps for all the locations. The entire process of weighting is differentiable and can be conveniently optimized by back-propagation.

In summary, the contributions of this study are three-fold as follows:

1. A new differentiable label assignment strategy named AutoAssign is proposed for dense object detection, which automatically assigns the positives and negatives for each instance. Moreover, the learnable paradigm enables it to transfer to different datasets and tasks without any modification.

2. Two weighting modules, i.e., center weighting and confidence weighting, are proposed to adaptively adjust the category-specific distribution as well as the instance-specific sampling strategy in both spatial and scale dimensions.

3. Extensive experiments with competitive results are carried out on the challenging MS COCO [12] dataset and other datasets from different domains, such as PASCAL VOC [3,4], Object365 [19] and WiderFace [22], demonstrating the effectiveness and broad applicability of AutoAssign.

2. Related Work

2.1. Fixed Label assignment

Classical object detectors sample positives and negatives with pre-determined strategies. Region Proposal Networks (RPN) in Faster R-CNN [17] preset several anchors with diverse scales and aspect ratios on each location. Then the assignment in both scale and spatial dimensions for each instance is guided by the anchor matching IoU. This anchor-based strategy quickly dominates modern detectors and extends to multi-scale output features such as YOLO [15,16], SSD [13], and RetinaNet [11]. Recent academic attention has been geared toward anchor-free detectors without anchor settings. FCOS [20] and its precursors [7,25,14] drop the prior anchor setting and directly assign the spatial positions around bounding box center of each object as positives. In scale dimension, they pre-define the scale range of each FPN [10] stage to assign instances. Both the anchor-based and anchor-free strategies follow center prior of data distributions, which indicates that spatial locations near the bounding box center are more likely to contain objects.

There are also some other anchor-free detectors [8,29,2,24,28] based on a different mechanism, which treats bounding boxes as key-points and transforms regression task to classification on heat maps. The characteristics of these detectors are distinct from detectors based on bounding box regression. Therefore they are out of the scope of this paper.

2.2. Dynamic Label assignment

As the fixed assigning strategies may be suboptimal for the various object distributions, recent detectors propose adaptive mechanisms to improve label assignment. GuidedAnchoring [21] leverages semantic features to guide the anchor settings and dynamically change the shape of anchors to fit various distributions of objects, while MetaAnchor [23] randomly samples anchors of any shape during training to cover different kinds of object boxes. Besides the modification of anchor prior, some works directly change the sampling for each object. FSAF [31] dynamically assigns each instance to the most suitable FPN feature level with minimal training loss. SAPD [30] reweights the positive anchors and applies an extra meta-net to select the proper FPN stages. FreeAnchor [27] constructs a
To accommodate to the distributions of different categories, we propose a category-wise and data-dependent weighting module named center weighting. It starts from the standard center prior and then learns the distribution of each category from data.

To get adapted to the appearance and scale of each instance, we further present an instance-wise weighting module called confidence weighting. It dynamically weights the positions in the spatial and scale dimensions based on the predicted confidences of each object.

Finally, we combine the two weighting modules to generate positive weights and negative weights for all the locations. Given an object \( n \), we formulate the training loss \( \mathcal{L}_n(\theta) \) after applying our entire weighting mechanism as follows:

\[
\mathcal{L}_n(\theta) = -\log\left(\sum_{i \in S_n} w_i^+ \mathcal{P}_i^+\right) - \sum_{i \in S_n} \log(w_i^- \mathcal{P}_i^-),
\]

where \( S_n \) denotes all locations inside the bounding box at all the scale levels. For a location \( i \in S_n \), its probabilities of being positive and negative are represented as \( \mathcal{P}_i^+ \) and \( \mathcal{P}_i^- \) respectively, which are predicted by the network. \( w_i^+ \) and \( w_i^- \) are weight maps generated by the proposed center weighting and confidence weighting.

### 3.2. Center Weighting

The prior distribution is a fundamental element for label assignment, especially in the early stage of training. In general, the distribution of objects is subject to the center prior. However, the objects from different categories, e.g., giraffe, and human, may have distinct distributions. Keeping sampling center positions cannot capture the different distributions of real-world instances. Preferably, for objects of different categories, adaptive center distributions are more desired.

Based on the center prior, we introduce a category-wise Gaussian-shape weighting function \( G \) with learnable parameters. “category-wise” means each category has its unique parameters \((\mu, \sigma)\) while all objects of the same cate-

### Table 1. Comparison of label assignment between different typical detectors. Results in terms of \( \text{AP} \) are reported on the MS COCO 2017 \textit{val} set, using ResNet-50 [5] as backbone. * denotes improved versions.

| Method               | Prior            | Instance Weighting | AP    |
|----------------------|------------------|--------------------|-------|
| RetinaNet [11]       | anchor           | size & IoU         | IoU   | 36.3  |
| FreeAnchor [27]      | anchor           | size & IoU         | top-k weighting, IoU | 38.7  |
| ATSS [26]            | anchor           | size & IoU         | top-k, dynamic IoU | 39.3  |
| GuidedAnchoring [21] | dynamic anchor   | size & IoU         | IoU   | 37.1  |
| FCOS* [20]           | center           | range              | radius| 38.7  |
| FSAF [31]            | anchor & center  | loss               | IoU & radius | 37.2  |
| AutoAssign (Ours)    | dynamic center   | weighting          | weighting | 40.5  |
Figure 3. Illustration of weighting in AutoAssign. Specifically, given an object, we first keep all the locations inside its bounding box as both positives and negatives. Then the proposed center weighting module and confidence weighting module dynamically generate the positive and negative weight maps, which can adjust the confidences at each location of being positive and negative. AutoAssign has the same architecture as FCOS. Thus only one proposal will be predicted at each location. The ImpObj branch shares weights with localization branch.

3.3. Confidence Weighting

Existing dynamic strategies \[31, 27, 9\] are designed with the fact that networks can easily learn proper samples with high confidence while tending to predict low confidence for inferior samples. Specifically, the confidence indicator is separately proved to be effective in the scale selection (loss indicator in \[31\]) and the spatial assignment (anchor confidence in \[27, 9\]). In confidence weighting, we propose a joint confidence indicator of both classification and localization to guide the weighting strategy in both spatial and scale dimensions.

3.3.1 Classification confidence

Given a spatial location \(i\), its confidence of classification can be naturally defined as \(P_i(cls|\theta)\), the probability of the object class that is directly predicted by the network. \(\theta\) denotes model parameters. However, in order to make sure all the proper locations are considered, we initially take all spatial locations inside boxes into account. As an object can hardly fill its bounding box completely, the initial positives set tends to contain a considerable part of background locations. If a location is, in fact, background, all class predictions in the location should be unreasonable. So taking too many inferior background locations as positives will damage detection performance.

To suppress false positives from the inferior locations, we introduce a novel Implicit-Objectness branch, which is shown in Fig. 3. It works just like the Objectness in RPN \[17\] and YOLO \[14\] as a binary classification task for foregrounds and backgrounds. But here we meet another issue of lacking explicit labels. RPN and YOLO adopt predefined assignment with consistent positive labels, while we need to find and emphasize proper positive labels dynamically.
We thus optimize the Objectness together with the classification branch, so it does not require explicit labels. That is why it is called Implicit-Objectness (ImpObj). For a location $i \in S_n$, after ImpObj is applied, the classification confidence $P_i(cls|\theta)$ can be defined as:

$$P_i(cls|\theta) = P_i(cls|obj, \theta)P_i(obj|\theta),$$

where the proposed ImpObj acts as $P_i(obj|\theta)$, which represents the probability of position $i$ being foreground(object) or background. $P_i(cls|obj, \theta)$ is the probability of position $i$ being a specific category given this position is known to be foreground or background. As demonstrated in Fig. 5, $P_i(cls|obj, \theta)$ is classification output. Its the same as classification branch in other detectors like RetinaNet [11].

To provide another view of understanding the novel ImpObj, we can take previous label assignment strategies as manually select foregrounds, that is setting $P_i(obj|\theta) = 1$ for positives and 0 for negatives. In this case, the classification confidence $P_i(cls|\theta) = P_i(cls|obj, \theta)$. While in AutoAssign, $P_i(obj|\theta)$ is dynamically decided by the network.

### 3.3.2 Joint confidence modeling

For generating unbiased estimation of each location towards positives/negatives, besides classification, we should also include the localization confidence. The typical outputs of localization are box offsets, which are hard to measure the regression confidence directly. We thus convert the localization loss $L_i^{loc}(\theta)$ into likelihood $P_i(loc|\theta)$, then we combine classification and regression likelihood together to get the joint confidence $P_i(\theta)$. It can be derived from loss $L_i(\theta)$ as follows. Without loss of generality, here we use Binary Cross-Entropy (BCE) loss for classification.

$$L_i(\theta) = L_i^{cls}(\theta) + \lambda L_i^{loc}(\theta)$$

$$= -\log(P_i(cls|\theta)) + \lambda \log(P_i(loc|\theta))$$

$$= -\log(P_i(cls|\theta)e^{-\lambda L_i^{loc}(\theta)})$$

$$= -\log(P_i(cls|\theta)P_i(loc|\theta))$$

$$= -\log(P_i(\theta)),$$

where $\lambda$ is the loss weight to balance between classification and localization.

### 3.3.3 Weighting function

Based on the joint confidence representation $P_i(\theta)$, we propose our confidence weighting function $C(P_i)$ in an exponential form to emphasize the locations with high confidence containing objects as:

$$C(P_i) = e^{\frac{P_i(\theta)}{\tau}},$$

where $\tau$ is the temperature coefficient, it controls the contributions of high and low confidence locations towards positive losses.

### 3.4 Weight Maps

#### 3.4.1 Positive weights

Intuitively, given an object $i$, for all locations inside its bounding box, we should focus on the proper locations with more accurate predictions. However, at the start of the training process, the network parameters are randomly initialized, making its predicted confidences unreasonable. Thus guiding information from prior is also critical. For location $i \in S_n$, we combine the category-specific prior $C(\hat{d}_i)$ from center weighting module and the confidence weighting module $C(P_i)$ together to generate the positive weights $w_i^+$ as:

$$w_i^+ = \frac{C(P_i)G(\hat{d}_i)}{\sum_{j \in S_n} C(P_j)G(\hat{d}_j)},$$

#### 3.4.2 Negative weights

As discussed above, a bounding box usually contains an amount of real-background locations, and we also need weighted negative losses to suppress these locations and eliminate false positives. Moreover, as the locations inside the boxes always tend to predict high confidence of positives, we prefer the localization confidence to generate the unbiased indicator of false positives. Paradoxically, the negative classification has no gradient for the regression task, which means the localization confidence should not be further optimized. Hence we use IoUs between each position’s predicted proposal and all objects to generate our negative weights $w_i^-$ as:

$$w_i^- = 1 - f\left(\frac{1}{1 - \text{iou}_i}\right),$$

in which iou$_i$ denotes max IoU between proposal of location $i \in S_n$ and all ground truth boxes. To be used as valid weights, we normalize $1/(1 - \text{iou}_i)$ into range [0, 1] by its value range by function $f$. This transformation sharpens the weight distributions and ensure that the location with highest iou receives zero negative loss. For all locations outside bounding boxes, $w_i^-$ is set to 1 because they are backgrounds for sure.

### 3.5 Loss function

By generating positive and negative weight maps, we achieve the purpose of dynamically assigning more appropriate spatial locations and automatically selecting the proper FPN stages for each instance. As the weight maps contribute to the training loss, AutoAssign tackles the label...
assignment in a differentiable manner. The final loss function $\mathcal{L}(\theta)$ of AutoAssign can be defined as follows:

$$
\mathcal{L}(\theta) = - \sum_{n=1}^{N} \log(\sum_{i \in S_n} w_i^+ P_i^+) - \sum_{j \in S} \log(w_j^- P_j^-),
$$

(12)

where $P^- = 1 - P(\text{cls} | \theta)$, and $n$ denotes the $n$-th ground truth. To ensure at least one location matches object $n$, we use weighted sum of all positive weights to get the final positive confidence. $S$ denotes all the locations at all the scales. Thus for a location inside bounding boxes, both positive and negative loss will be calculated with different weights. This is a huge difference from all other label assignment strategies. To handle the imbalance problem among negative locations, Focal Loss is applied.

Although the magnitude of positive and negative weights might be different according to Eq. 10, 11 the positive loss and negative loss are calculated independently.

### 4. Experiments

Experiments are mainly evaluated on the challenging MS COCO 2017 [12] benchmark, which contains around 118k images in the train set, 5k in the val set and 20k in the test-dev set. We report analyses and ablation studies on the val set and compare our final results with other methods on the test-dev set.

#### 4.1. Implementation Details

We use ResNet-50 [6] with FPN [10] as backbone for all experiments if not specifically pointed out. We initialize the backbone with weights pre-trained on ImageNet [11]. Followed the common practice, all models are trained for 1× schedule named in [5], i.e., 90k iterations with an initial learning rate of 0.01, which is then divided by 10 at 60k and 80k iterations, with the weight decay of 0.0001 and the momentum of 0.9. Horizontal image flipping is utilized in data augmentation. For all ablation studies we use an image scale of 800 pixels for training and testing, unless otherwise specified. We set $\tau = 1/3$ in Eq. 5 and $\lambda = 5.0$ in Eq. 4. We apply Focal Loss [11] with $\alpha = 0.25$ and $\gamma = 2.0$ for negative classification and GIOU loss [18] for box localization. Non-maximum suppression (NMS) with IoU threshold 0.6 is applied to merge the results.

#### 4.2. Ablation Studies

##### 4.2.1 Center weighting and confidence weighting

To demonstrate the effectiveness of the two key components, we construct the positives weights $w_i^+$ using center weighting and confidence weighting separately, while keeping the negatives weighting unchanged. As shown in Table 2, it can be seen that center weighting brings relatively significant performance gain, suggesting that the prior distribution is critical for guiding the training. Besides, confidence weighting further improves the accuracy as it dynamically changes the strategy for each object in both spatial and scale dimensions.

| Center | Conf | AP  | AP$_{50}$ | AP$_{75}$ | AP$_{S}$ | AP$_{M}$ | AP$_{L}$ |
|--------|------|-----|-----------|-----------|---------|---------|---------|
| ✓      | ✓    | 17.7| 30.9      | 18.1      | 15.7    | 24.2    | 23.3    |
| ✓      |      | 37.7| 57.4      | 40.6      | 20.3    | 41.4    | 52.0    |
| ✓      | ✓    | 40.5| 59.8      | 43.9      | 23.1    | 44.7    | 52.9    |

Table 2. Contributions of center weighting and confidence weighting. “Center” means center weighting, and “Conf” indicates confidence weighting. The 17.7 mAP baseline is the start point of AutoAssign, which can be seen as removing $w^+$ and $w^-$ from Eq 12. Other detectors, like RetinaNet, can also be implemented by adding modules to this simple baseline.

To better understand the working mechanism of the two proposed modules, we visualize the positive weight maps separately in each FPN stage from a well-trained detector. From Fig. 4, we can see that the center weighting is applied to all stages of FPN to achieve a coarse weighting based on the category-specific center prior. Then the confidence weighting performs spatial and scale assignments for each instance. Objects of different shapes and different sizes are assigned to its appropriate spatial locations and suitable scale stages automatically. Our final positive weight maps that combine the effect of center weighting and confidence weighting are shown in the third row.

##### 4.2.2 Analysis of center weighting

To analyze the design of the center weighting, we compare different prior distributions in Table 3. We denote the Gaussian-shape function $G$ without learnable parameters as “fixed”, while “shared” means only one group of learnable $\vec{\mu}$ and $\vec{\sigma}$ is shared among all categories. Compared to the fixed prior, “shared” prior slightly drops the AP by 0.1%, while our category-wise prior increases the AP of 0.2% on MS COCO. As MS COCO contains 80 categories with a huge amount of data, its object distribution generally falls into a normal distribution. Thus the total improvement of category-wise prior is not significant. But when we look into some classes with unique distributions, e.g., bear, surfboard and hotdog, the improvements are notable.

This can also be evidenced by the visualization of the learned priors for each category in Fig. 5. We mark white points as the center of bounding boxes and red points as the center of learned priors. We can see that in the categories of parking meter and hotdog, the learned centers $\vec{\mu}$ shift down as these categories tend to have more essential clues at the bottom half. Moreover, the category-specific $\vec{\sigma}$ is also changed for each category. For the categories of
Figure 4. Visualization of center weighting, confidence weighting, and positive weights. From the middle row, objects of different sizes can be automatically assigned to their appropriate FPN stages.

| Method          | ImpObj | AP  | AP_{50} | AP_{75} | AP_{S} | AP_{M} | AP_{L} |
|-----------------|--------|-----|---------|---------|--------|--------|--------|
| RetinaNet [11]  | ✓      | 35.9| 55.9    | 38.2    | 22.9   | 42.0   | 49.5   |
| FCOS* [20]      | ✓      | 38.8| 57.6    | 42.2    | 38.5   | 58.2   | 42.3   |
| FreeAnchor [27] | ✓      | 38.3| 57.1    | 41.2    | 38.5   | 57.6   | 41.5   |
| ATSS [26]       | ✓      | 39.3| 57.8    | 42.6    | 39.7   | 58.4   | 42.9   |
| AutoAssign      | ✓      | 39.4| 58.7    | 42.5    | 40.5   | 59.8   | 43.9   |

Table 5. Contribution of ImpObj to typical detectors. The number in brackets indicates the contribution of ImpObj to corresponding detectors. For example, ImpObj brings 0.2% improvements to RetinaNet. Bold fonts indicate the best performance.

4.2.3 Analysis of confidence weighting

| Confidence      | AP  | AP_{50} | AP_{75} | AP_{S} | AP_{M} | AP_{L} |
|-----------------|-----|---------|---------|--------|--------|--------|
| $\mathcal{P}(cls)$-only | 38.7| 59.9    | 41.6    | 22.9   | 42.0   | 49.5   |
| $\mathcal{P}(loc)$-only | 39.7| 58.4    | 43.1    | 22.4   | 43.6   | 51.6   |
| no-obj          | 39.4| 59.7    | 42.5    | 22.4   | 43.5   | 50.7   |
| explicit-obj    | 39.5| 58.8    | 42.3    | 21.6   | 43.4   | 52.2   |
| AutoAssign      | 40.5| 59.8    | 43.9    | 23.1   | 44.7   | 52.9   |

Table 4. Comparison of different choices for confidence weighting. $\mathcal{P}(cls)$-only means only use $\mathcal{P}(cls)$ for confidence weighting. “no-obj” means do not use ImpObj for $\mathcal{P}(cls)$, “explicit-obj” means give the object-ness branch individual supervision, rather than sharing with classification.

We evaluate the effectiveness of classification confidence

We also notice Implicit-Objectness is a universal design
which can be applied to other detectors. As shown in Table 5 due to the constrained number of positive locations (e.g. top k anchors in FreeAnchor), the contribution of ImpObj to those detectors are minor. This indicates that ImpObj is more suitable for fully dynamic assignment.

4.3. Comparison with State-of-the-art

We compare AutoAssign with other state-of-the-art detectors on MS COCO test-dev set. We adopt 2× schedule following the previous works [20, 27, 26]. Results are shown in Table 6. Our AutoAssign with ResNet-101 backbone achieves 44.5% AP, outperforming all state-of-the-art one-stage detectors with the same backbone as we known. By changing the backbone and training setting the same to other methods, our method consistently outperforms other counter-parts. With a wider range of multi-scale training and multi-scale testing strategy, our best model achieves 52.1% AP, which outperforms all existing one-stage detectors.

4.4. Generalization

To demonstrate the generalization ability, we evaluate our AutoAssign with several typical label assign strategies on different detection tasks, including general object detection (PASCAL VOC [3, 4], Objects365 [19]) and face detection (WiderFace [22]). In these experiments we keep the assignment strategy of each method (like anchor scale and
AutoAssign with differential label assignment can adapt to different datasets and achieve superior performance without any adjustment.

5. Conclusions

In this paper, we propose a differentiable label assignment strategy named AutoAssign. It tackles label assignment in a fully data-driven manner by automatically determine the positives/negatives in both spatial and scale dimen-

Table 6. Performance comparison with state-of-the-art one-stage detectors on MS COCO 2017 test-dev set. All results listed adopt multi-scale training. † indicates multi-scale training with wider range [480, 960] used in [27]. ‡ indicates multi-scale testing. * indicates improved versions

| Method        | Iteration | AP  | AP_{50} | AP_{75} | AP_S | AP_M | AP_L |
|---------------|-----------|-----|---------|---------|------|------|------|
| ResNet-101    | 135k      | 39.1| 59.1    | 42.3    | 21.8 | 42.7 | 50.2 |
| RetinaNet [11]| 180k      | 41.5| 60.7    | 45.0    | 24.4 | 44.8 | 51.6 |
| FCOS [11]     | 180k      | 43.1| 62.2    | 46.4    | 24.5 | 46.1 | 54.8 |
| FreeAnchor [27]| 180k    | 43.5| 63.6    | 46.5    | 24.9 | 46.8 | 54.6 |
| SAPD [30]     | 180k      | 43.6| 62.1    | 47.4    | 26.1 | 47.0 | 53.6 |
| ATSS [26]     | 180k      | 44.5| 64.3    | 48.4    | 25.9 | 47.4 | 55.0 |
| AutoAssign (Ours) | 180k | 44.5| 64.3    | 48.4    | 25.9 | 47.4 | 55.0 |
| ResNet-64x4d-101 | 180k | 44.7| 64.1    | 48.4    | 27.6 | 47.5 | 55.6 |
| FCOS* [20]    | 180k      | 44.9| 64.3    | 48.5    | 26.8 | 48.3 | 55.9 |
| FreeAnchor [27]| 180k    | 45.4| 65.6    | 48.9    | 27.3 | 48.7 | 56.8 |
| SAPD [30]     | 180k      | 45.6| 64.6    | 49.7    | 28.5 | 48.9 | 55.6 |
| ATSS [26]     | 180k      | 46.5| 66.5    | 50.7    | 28.3 | 49.7 | 56.6 |
| AutoAssign (Ours) | 180k | 46.5| 66.5    | 50.7    | 28.3 | 49.7 | 56.6 |
| ResNet-64x4d-101-DCN | 180k | 47.4| 67.4    | 51.1    | 28.1 | 50.3 | 61.5 |
| SAPD [30]     | 180k      | 47.7| 66.5    | 51.9    | 29.7 | 50.8 | 59.4 |
| ATSS [26]     | 180k      | 48.3| 67.4    | 52.7    | 29.2 | 51.0 | 60.3 |
| AutoAssign (Ours) | 180k | 49.5| 68.7    | 54.0    | 29.9 | 52.6 | 62.0 |
| AutoAssign (Ours)† | 180k | 52.1| 69.6    | 58.0    | 33.9 | 54.0 | 64.0 |

Results are shown in Table 7. We can see that the performance of other methods with fixed or partly fixed assigning strategies are unstable on different datasets. Although they achieve excellent performance on certain datasets, their accuracies on the other dataset may be worse. This proves that the label assignment strategy of these methods has a low robustness and need to be adjusted cautiously. In contrast, aspect ratios) unchanged and only adjust the training settings following the common paradigm of each dataset.
In Table 7, we present a performance comparison with typical detectors on PASCAL VOC, Objects365, and WiderFace. * indicates improved versions.

| Method          | PASCAL VOC | Objects365 | WiderFace |
|-----------------|------------|------------|-----------|
|                 | AP | AP50 | AP75 | AP | AP50 | AP75 | AP | AP50 | AP75 |
| RetinaNet [11]  | 55.4 | 81.0 | 60.1 | 18.4 | 28.4 | 19.6 | 46.7 | 83.7 | 47.1 |
| FCOS* [20]      | 55.4 | 80.5 | 61.1 | 20.3 | 29.9 | 21.9 | 48.1 | 87.1 | 48.4 |
| FreeAnchor [27] | 56.8 | 81.1 | 62.1 | 21.4 | 31.5 | 22.8 | 46.3 | 81.6 | 47.5 |
| ATSS [26]       | 56.6 | 80.7 | 62.6 | 20.7 | 30.0 | 22.4 | 48.9 | 87.1 | 49.7 |
| AutoAssign (Ours) | **57.9** | **81.6** | **64.1** | **21.6** | **31.7** | **23.2** | **49.5** | **88.2** | **49.9** |

Table 7. Performance comparison with typical detectors on PASCAL VOC, Objects365, and WiderFace. * indicates improved versions.

AutoAssign is built from scratch and has no traditional components, e.g., anchors, making it fully learnable. It achieves consistent improvement to all the existing sampling strategies by ~1% AP with various backbones on MS COCO. Besides, extensive experiments on other datasets demonstrate that AutoAssign can conveniently transfer to other datasets and tasks without additional modification.

This new label assignment strategy also comes with new challenges, for example, current weighting mechanism is not simple enough and can be further simplified, which will be left for future work.

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