

Generative Adversarial Guided Learning for Domain Adaptation (Supplementary Materials)

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1 CNN Architecture

Table 1 and Table 2 show the CNN architecture of classification model D , which is the same as in [14]. The numbers of convolution kernels (A, B, C) are (64, 64, 64) for the small CNN and (96, 192, 192) for the large CNN. Table 3 shows the architecture of generator G . All activation functions after convolution and dense layer are leaky ReLU with $\alpha = 0.1$ if not specified in the tables. Batch normalization is applied before activation in D_f , D_y , and G .

Layer type	Output size	model indice
Input image	$32 \times 32 \times 3$	D_f
Instance normalization	$32 \times 32 \times 3$	D_f
Conv. $3 \times 3 \times A$, stride 1, pad 1	$32 \times 32 \times A$	D_f
Conv. $3 \times 3 \times A$, stride 1, pad 1	$32 \times 32 \times A$	D_f
Conv. $3 \times 3 \times A$, stride 1, pad 1	$32 \times 32 \times A$	D_f
Max-pooling 2×2 , stride 2	$16 \times 16 \times A$	D_f
Dropout ,rate=0.5	$16 \times 16 \times A$	D_f
Gaussian noise, $\sigma = 1$	$16 \times 16 \times A$	D_f
Conv. $3 \times 3 \times B$, stride 1, pad 1	$16 \times 16 \times B$	D_f
Conv. $3 \times 3 \times B$, stride 1, pad 1	$16 \times 16 \times B$	D_f
Conv. $3 \times 3 \times B$, stride 1, pad 1	$16 \times 16 \times B$	D_f
Max-pooling 2×2 , stride 2	$8 \times 8 \times B$	D_f
Dropout ,rate=0.5	$8 \times 8 \times B$	D_f
Gaussian noise, $\sigma = 1$	$8 \times 8 \times B$	D_f
Conv. $3 \times 3 \times C$, stride 1, pad 1	$8 \times 8 \times C$	D_y
Conv. $3 \times 3 \times C$, stride 1, pad 1	$8 \times 8 \times C$	D_y
Conv. $3 \times 3 \times C$, stride 1, pad 1	$8 \times 8 \times C$	D_y
Global pooling	$1 \times 1 \times C$	D_y
Dense-softmax	#. of class	D_y

Table 1: CNN architecture of feature extractor D_f and label predictor D_y .

Layer type	Output size	model indice
Output of D_f	$8 \times 8 \times B$	D_f
Reshape	$1 \times 64 \times B$	D_a
Dense-relu, 100 units	1×100	D_a
Dense-sigmoid, 1 unit	1	D_a

Table 2: CNN architecture of domain discriminator D_a .

Layer type	Output size	model indice
Input noise z	1×100	G
Dense, 8192 units	1×8192	G
Reshape	$4 \times 4 \times 512$	G
Transposed Conv. $5 \times 5 \times 256$, stride 2	$8 \times 8 \times 256$	G
Transposed Conv. $5 \times 5 \times 128$, stride 2	$16 \times 16 \times 128$	G
Transposed Conv.-tanh $5 \times 5 \times 3$, stride 2	$32 \times 32 \times 3$	G

Table 3: CNN architecture of generator G .

2 Hyper-parameters

Table 4 shows the hyper-parameters of each task.

Task.	λ_a	λ_u
SVHN \rightarrow MNIST	10^{-2}	0.5
MNIST \rightarrow SVHN	10^{-2}	0.1
Syn-Num \rightarrow SVHN	10^{-2}	1.0
MNIST \rightarrow MNIST-M	10^{-2}	0.5
CIFAR \rightarrow STL	10^{-2}	0.1
STL \rightarrow CIFAR	10^{-2}	0.1
Syn-Signs \rightarrow GTSRB	0	0.5

Table 4: Hyper-parameters on seven UDA tasks.

3 Visualization

References

- [1] R. Shu, H. H. Bui, H. Narui, and S. Ermon. A DIRT-T approach to unsupervised domain adaptation. In *Proc. International Conference on Learning Representation*, 2018.

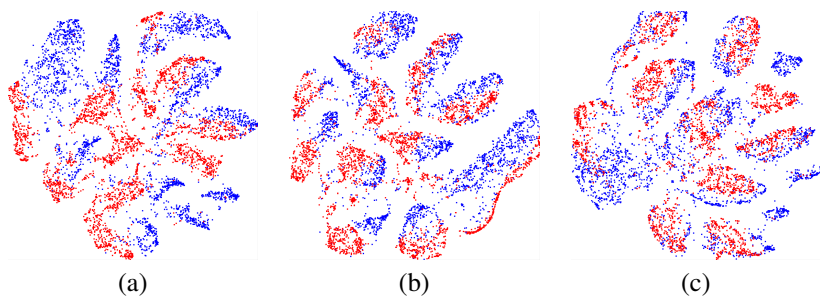


Figure 1: Visualization of feature representation from SVHN (blue) \rightarrow MNIST (red) task via t-SNE. (a): DNN-SO; (b): DANN-O; (c): GAGL.

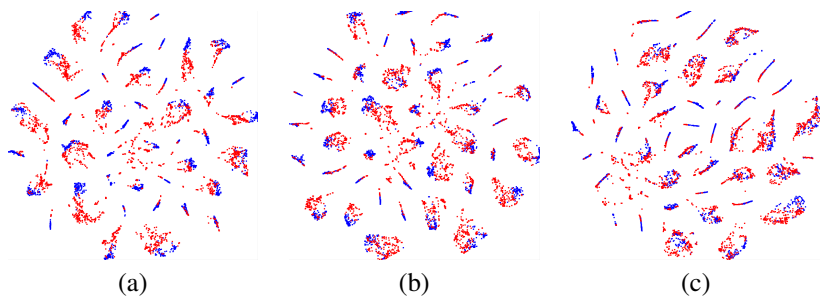


Figure 2: Visualization of feature representation from Syn-Sigs (blue) \rightarrow GTSRB (red) task via t-SNE. (a): DNN-SO; (b): DANN-O; (c): GAGL.

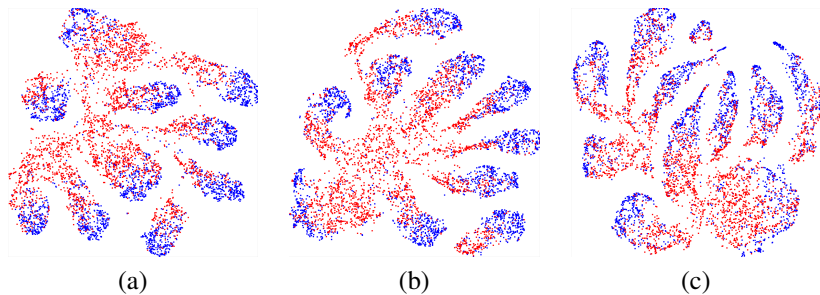


Figure 3: Visualization of feature representation from Syn-Num (blue) \rightarrow SVHN (red) task via t-SNE. (a): DNN-SO; (b): DANN-O; (c): GAGL.