Lesson 8 & 9:

* Classification is the hard part, bounding boxes are easy (even though resnet specializes in the former)
* Be careful with data augmentation. We should use it to get best results, but many common augmentations will not work for us because the orientation of the car matters.
* Better to share layers if possible, though not necessarily \*all\* the layers (intuitive, yes, but apparently also true)
* Create custom data loader class to return tuple of outputs
* Convolution “Receptive Field” (for understanding convnet inner workings)
* Background class acceptable, though especially with multi-object classification (We probably don’t care so much about classifying all the objects in our view. If we just classify the “main” object, the one closest to our camera presumably, we get the important information. Either we see the car and we’re in good shape, or we see something else and we need to take corrective action).
* Adding a custom head onto an existing model architecture is generally a good design idea (if you need the specialization)
* [Stop at 50 minutes, gets too specific into Multi image classifying and all its problems]

Lesson 11:

* Sequence to Sequence models: interesting potential applications
  + Follower => Follower, i.e. giving some sort of tendency to for “less jittery actions”
  + Leader => Follower, essentially translating leader commands into follower commands
* Alternatively general LSTM / GRU layers added may suffice