

Experimental Protocol

Wed Jul 25 19:55:29 2018

experiment group:	tless_nobn
experiment name	obj5
evaluation name	25_07_18_icp_bbtest
test dataset	tless_primesense

1 Train Config

[Paths] MODEL_PATH: /net/rmc-lx0314/home_local/sund_ma/data/t-less/models_reconst/obj_05.ply
BACKGROUND_IMAGES_GLOB: /net/rmc-lx0314/home_local/sund_ma/data/VOCdevkit/VOC2012/JPEGImages

[Dataset] MODEL: reconst H: 128 W: 128 C: 3 RADIUS: 700 RENDER_DIMS: (720, 540)
K: [1075.65, 0, 720/2, 0, 1073.90, 540/2, 0, 0, 1] VERTEX_SCALE: 1 ANTIALIASING: 8
PAD_FACTOR: 1.2 CLIP_NEAR: 10 CLIP_FAR: 10000 NOOF_TRAINING_IMGS: 20000 NOOF_BG_IMGS:
15000

[Augmentation] REALISTIC_OCCLUSION: False CROP_OFFSET_SIGMA: 20 CODE: Sequential([Sometimes(0.5, Affine(scale=(1.0, 1.2))), Sometimes(0.5, CoarseDropout(p=0.2, size_percent=0.05)), Sometimes(0.5, GaussianBlur(1.2*np.random.rand())), Sometimes(0.5, Add((-25, 25), per_channel=0.3)), Sometimes(0.3, Invert(0.2, per_channel=True)), Sometimes(0.5, Multiply((0.6, 1.4), per_channel=0.5)), Sometimes(0.5, Multiply((0.6, 1.4))), Sometimes(0.5, ContrastNormalization((0.5, 2.2), per_channel=0.3))], random_order=False)

[Embedding] EMBED_BB: True MIN_N_VIEWS: 1000 NUM_CYCLO: 36

[Network] BATCH_NORMALIZATION: False AUXILIARY_MASK: False VARIATIONAL: 0
LOSS: L2 BOOTSTRAP_RATIO: 4 NORM_REGULARIZE: 0 LATENT_SPACE_SIZE: 128 NUM_FILTER:
[128, 256, 512, 512] STRIDES: [2, 2, 2, 2] KERNEL_SIZE_ENCODER: 5 KERNEL_SIZE_DECODER:
5

[Training] OPTIMIZER: Adam NUM_ITER: 30000 BATCH_SIZE: 64 LEARNING_RATE: 2e-4
SAVE_INTERVAL: 10000

[Queue] NUM_THREADS: 10 QUEUE_SIZE: 50

2 Evaluation Config

[METHOD] method = ae

[DATA] dataset = tless cam_type = primesense scenes = [] obj_id = 5

[BBOXES] estimate_bbs = True external = /net/rmc-lx0318/home_local/public/experiments/keras-retinanet/t-less.test_primesense_eval/detections ckpt = /home_local/sund_ma/ssd_ws/checkpoints/tless_real_train_voc pad_factor = 1.2 single_instance = True

[EVALUATION] gt_trans = False icp = True compute_errors = False evaluate_errors = False top_n_eval = 0

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[METRIC] error_thres = 'vsd':0.3,'cou':0.5,'te':5.0,'re':5.0 error_thresh_fact = 'add':0.1,'adi':0.1
error_type = ['vsd','re','te'] top_n = 1 vsd_delta = 15 vsd_tau = 20 vsd_cost = step
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[PLOT] nearest_neighbors = False scene_with_estimate = False reconstruction = False cum_t_error_hist
= True cum_r_error_hist = True cum_vsd_error_hist = True vsd_occlusion = True r_error_occlusion
= True embedding_pca = True animate_embedding_pca = False viewsphere = True reconstruction_test_batch = True
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