

PhD

SSD Single Shot MultiBox Detector eccv16_ax16_12

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It turns out that the default boxes of SSD are indeed identical to the anchor boxes of faster RCNN except that these are applied to several feature maps of different sizes instead of the single feature map used in the latter;

network is constructed by adding several convolutional feature layers to a truncated version of the base network like VGG 16;

Each feature map is divided into a regular grid of cells and a fixed number of default boxes are associated with each such cell;

Similar to faster RCNN, this paper does not make it clear either as to exactly how the ground truth boxes defined in the space of the original images are mapped to all of the different sized feature maps so that overlap can be computed between them and the default boxes;

seems likely that both of them use simple linear scaling based on the size of the feature map;

its default box labelling strategy seems to be pretty much the same as faster RCNN too;