Self-Driving Cars

Lecture 10 – Object Detection

Prof. Dr.-Ing. Andreas Geiger

Autonomous Vision Group

University of Tübingen / MPI-IS

Agenda

10.1 Introduction

10.2 Performance Evaluation

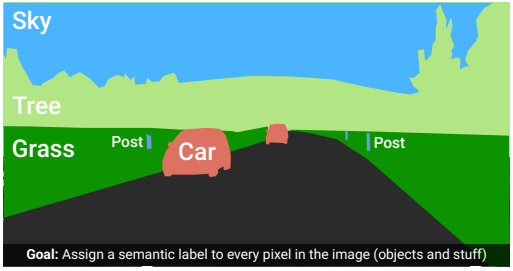
10.3 Sliding Window Object Detection

10.4 Region Based CNNs

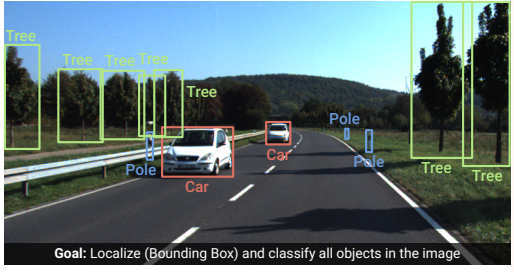
10.5 3D Object Detection

10.1
Introduction

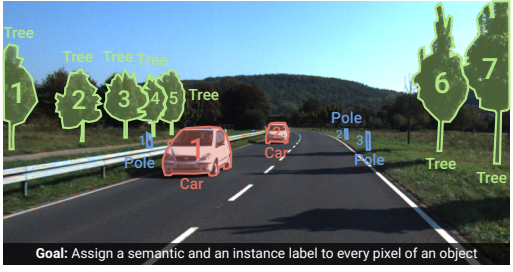
Image Classification



Semantic Segmentation

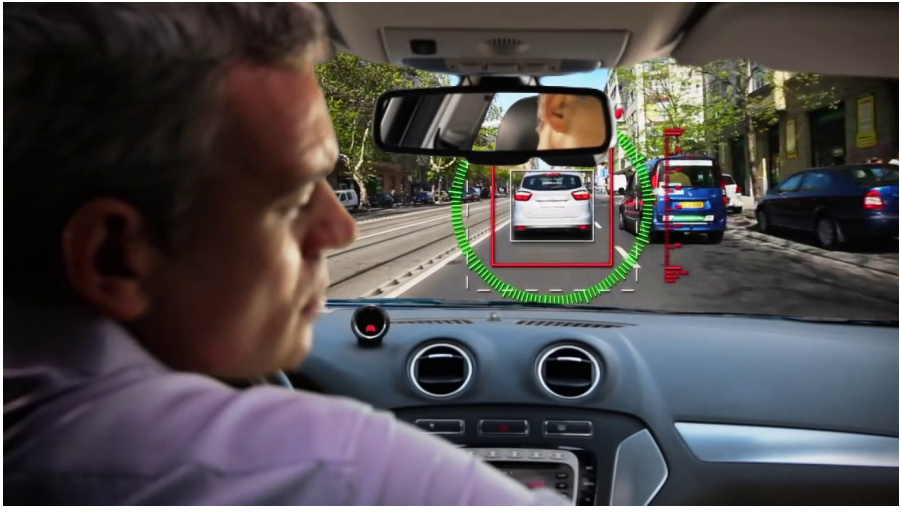


Object Detection



Instance Segmentation

Motivation

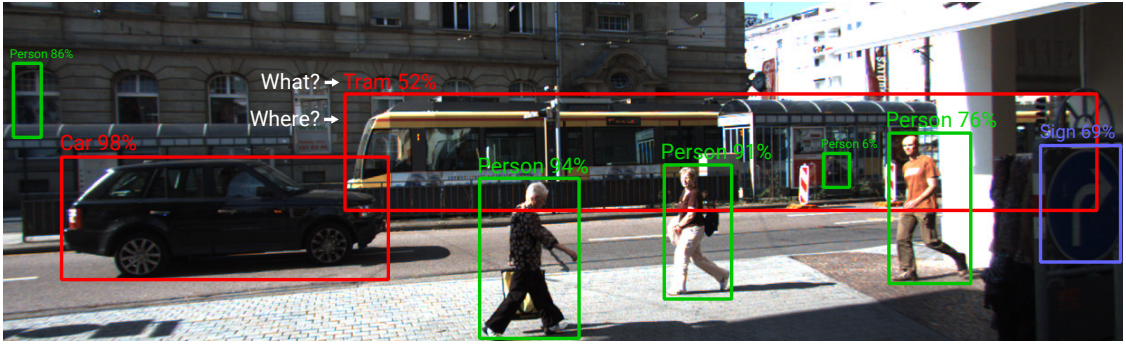


https://www.youtube.com/watch?v=HXpiyLUEOOY

Motivation

https://www.youtube.com/watch?v=tiwVMrTLUWg

Problem Setting



Problem Setting:

- **Input:** RGB Image or laser range scan.
- **Output:** Set of 2D/3D bounding boxes with category label and confidence
- There are many (∞) possible boxes and even the number of objects is unknown

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Challenges

Challenges: Large Number of Image Categories

Slide Credits: Koenderink, Lazebnik, Fei-Fei.

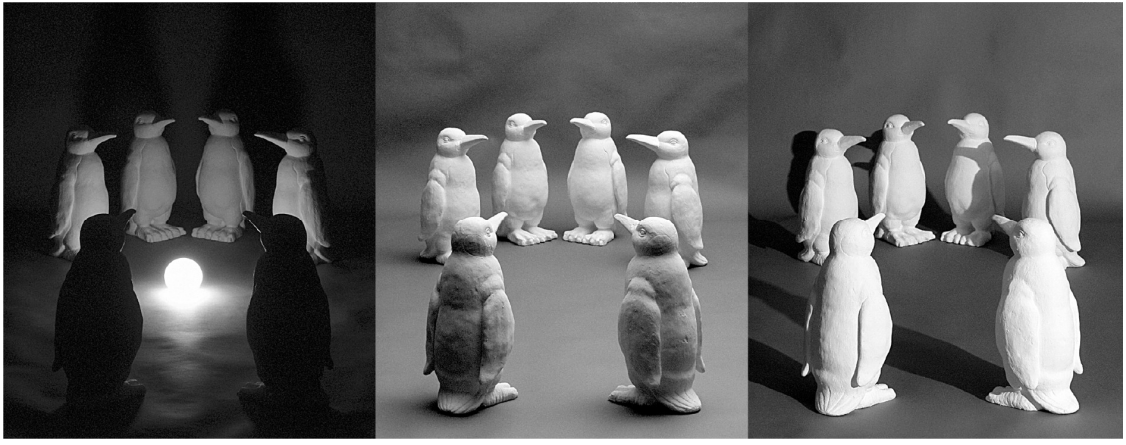
Challenges: Intra-class Variation

Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Challenges: Viewpoint Variation

Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Challenges: Illumination Changes

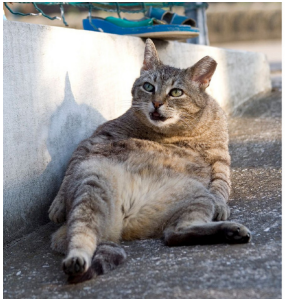
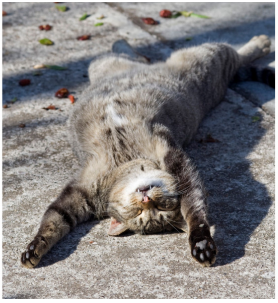


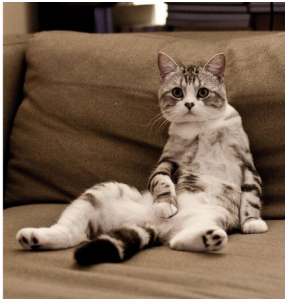
Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Challenges: Background Clutter

Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Challenges: Deformation



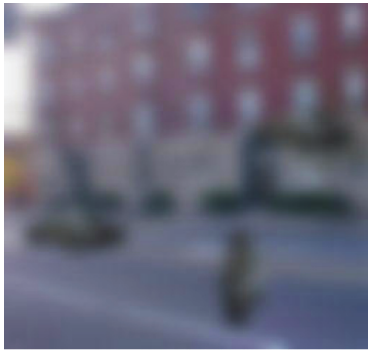
Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Challenges: Occlusion



Slide Credits: Koenderink, Lazebnik, Fei-Fei.

Context Matters


- Contextual information is important! What do you see here?
- But it can also be misleading ...

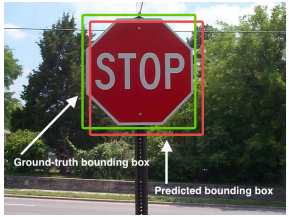
Torralba, Murphy and Freeman: Using the forest to see the trees: exploiting context for visual object detection and localization. Commun. ACM, 2010.

Context Matters

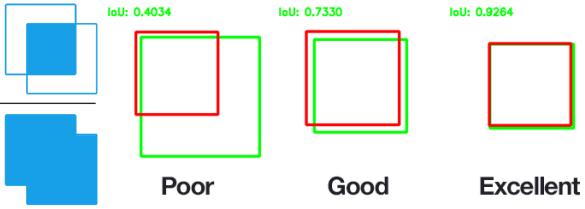
Torralba, Murphy and Freeman: Using the forest to see the trees: exploiting context for visual object detection and localization. Commun. ACM, 2010.

10.2
Performance Evaluation

How to Measure Detection Performance?



$$IoU = \frac{\text{Area of Overlap}}{\text{Area of Union}}$$



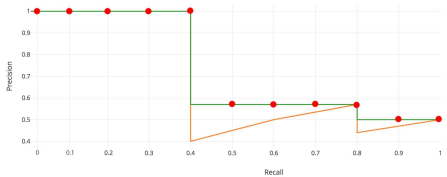
Measuring Bounding Box Alignment wrt. Ground Truth:

- IoU = Intersection-over-Union (predicted bbox vs. true bbox)
- Detection considered successful if IoU > 0.5
- How to fairly measure detection performance in case of multiple objects?
- Number of detections depends on detector threshold and is detector specific

How to Measure Detection Performance?

Average Precision Metric:

1. Run detector with varying thresholds
2. Assign detections to closest object
3. Count TP, FP, FN
4. Compute **Average Precision (AP)**



True Positives TP: Number of objects correctly detected (IoU>0.5)

False Negatives FN: Number of objects not detected (IoU<0.5)

False Positives FP: Wrong detections

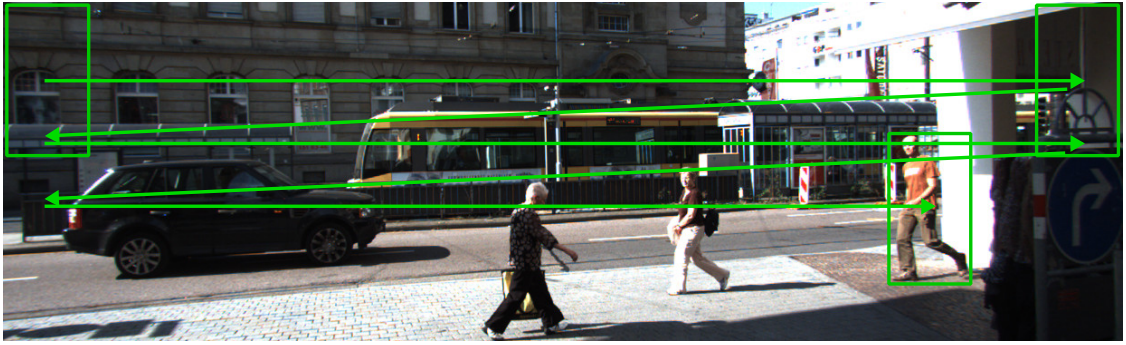
$$\text{Precision } P = \frac{TP}{TP + FP}$$

$$\text{Recall } R = \frac{TP}{TP + FN}$$

$$\text{Avg. Prec. } AP = \frac{1}{11} \sum_{R \in \{0,\ldots,1\}} \max_{R' \geq R} P(R')$$

10.3
Sliding Window Object Detection

Sliding Window Object Detection



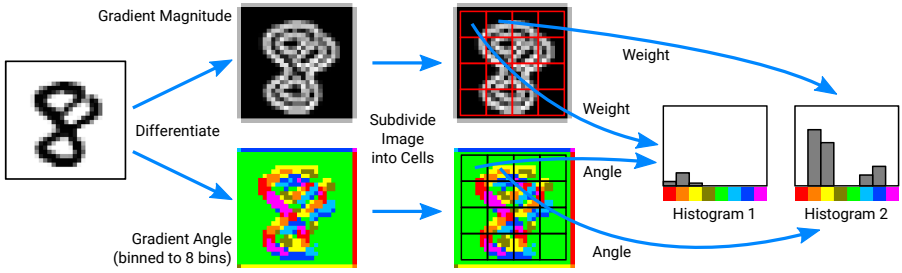
Sliding Window Detection:

- Run **sliding window** of fixed size over the image; extract features for each window
- **Classify each crop** (object vs. background) using SVM, random forest, boosting, ..
- **Search across aspect ratios/scales** to recover objects of varying size/distance
- **Non-maxima suppression** (=clustering) to retrain only 1 prediction per object

Histograms of Oriented Gradients

Which feature space to use?

- Simplest: RGB pixel space $\Rightarrow$ neither viewpoint nor illumination invariant
- Better: Histograms of Oriented Gradients (HoG) (defacto standard for $>$10 years)
  - Idea: represent patches with histograms (gradient angles weighted by magnitude)



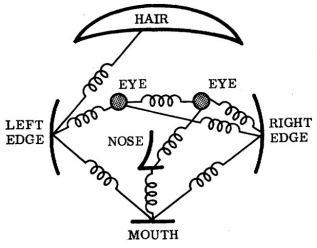
- HoG is invariant to small deformations (translation, scale, rotation, perspective)

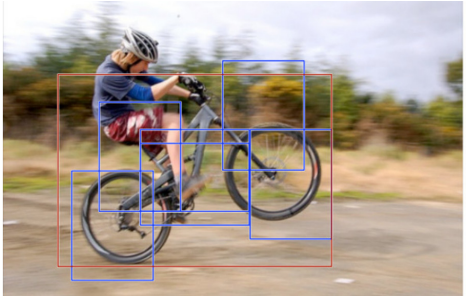
Dalal and Triggs: Histograms of Oriented Gradients for Human Detection. CVPR, 2005.

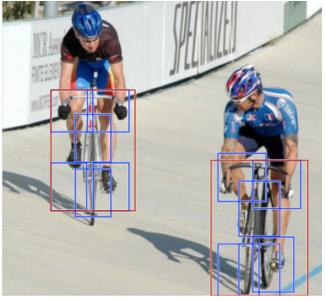
Part Based Models

Part-based Models:

- Idea: Model object based on its parts, **model distribution of part configurations**
- Allows for even more invariance (non-rigid deformations etc.)
- However: **slower inference** and not much gain wrt. multi-view HoG models

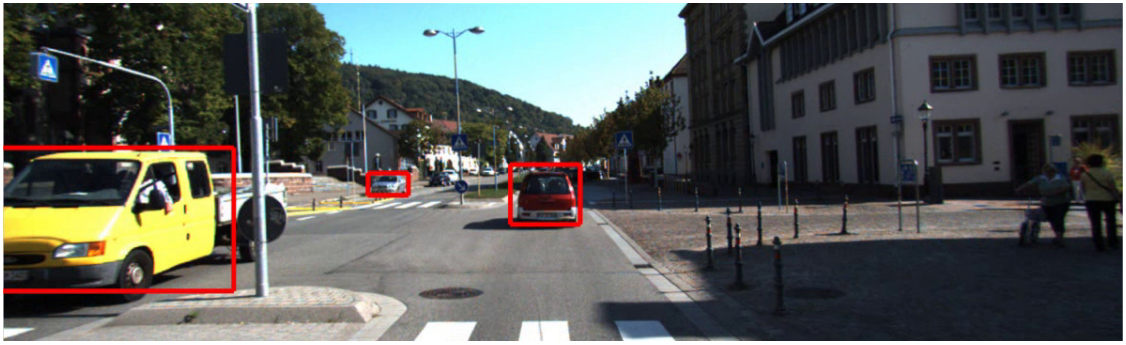






Object Detection with Discriminatively Trained Part Based Models. Felzenszwalb, Girshick, McAllester and Ramanan. PAMI, 2010.

Results on KITTI



Object Detection with Discriminatively Trained Part Based Models. Felzenszwalb, Girshick, McAllester and Ramanan. PAMI, 2010.

10.4
Region Based CNNs

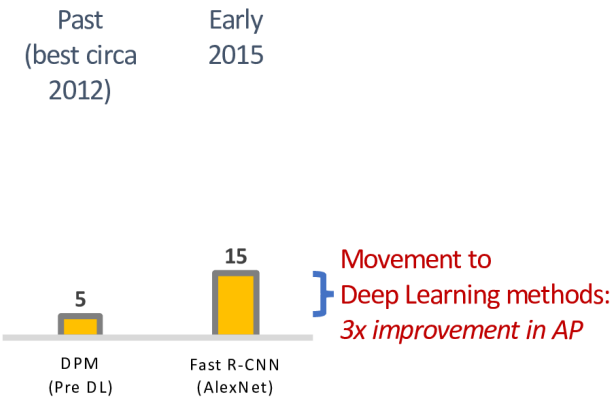
Recognition - A Success Story?

Classical approaches **haven't lead to major breakthroughs:** only for specific non-safety-critical tasks (e.g., face detection), they have seen great success. **Why?**

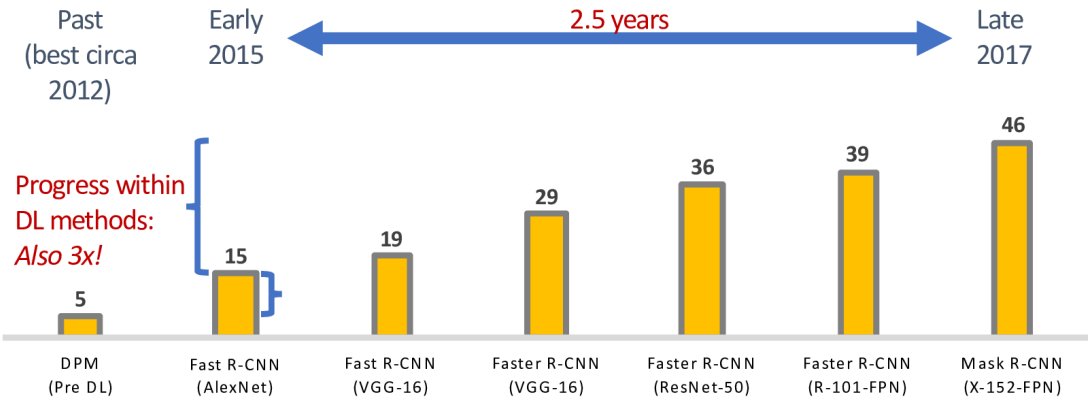
- Computer vision features are very difficult to hand-engineer
- It is unclear how a good representation should look like
- Furthermore, sliding window approaches are slow in practice
- Inference in complicated part-based models is even slower
- Computation is often not efficiently re-used
- But: deep learning has changed this ..

Hand-crafted Representations vs. Learned Representations

Hand-crafted Representations vs. Learned Representations



Hand-crafted Representations vs. Learned Representations



Object Detection with Deep Neural Networks

Slide Credits: Ross Girshick

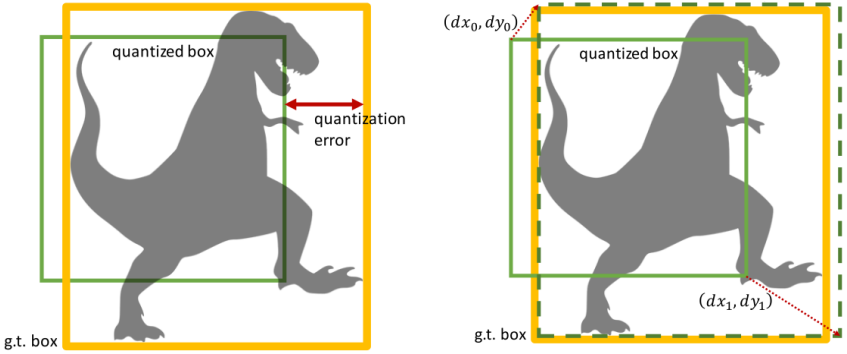
Proposal-based Object Detection

How can we detect objects using deep neural networks?

- Naïve idea: Classify all possible boxes in the image using a classification network
- Problem: Too many boxes to classify (even if space is discretized)
- Better idea:
  1. **Detect** $\sim 2k$ candidate bounding boxes that might contain an object (quantize)
     $\Rightarrow$Choose set such that it is overcomplete (i.e., it should contain all boxes)
  2. **Classify and refine** the location the boxes using a deep neural network (regress)
- This approach is called a proposal-based (2-stage) object detector
- Note: We have split the original object detection problem into 2 proxy tasks

Girshick, Donahue, Darrell and Malik: Rich feature hierarchies for accurate object detection and semantic segmentation. CVPR, 2014.

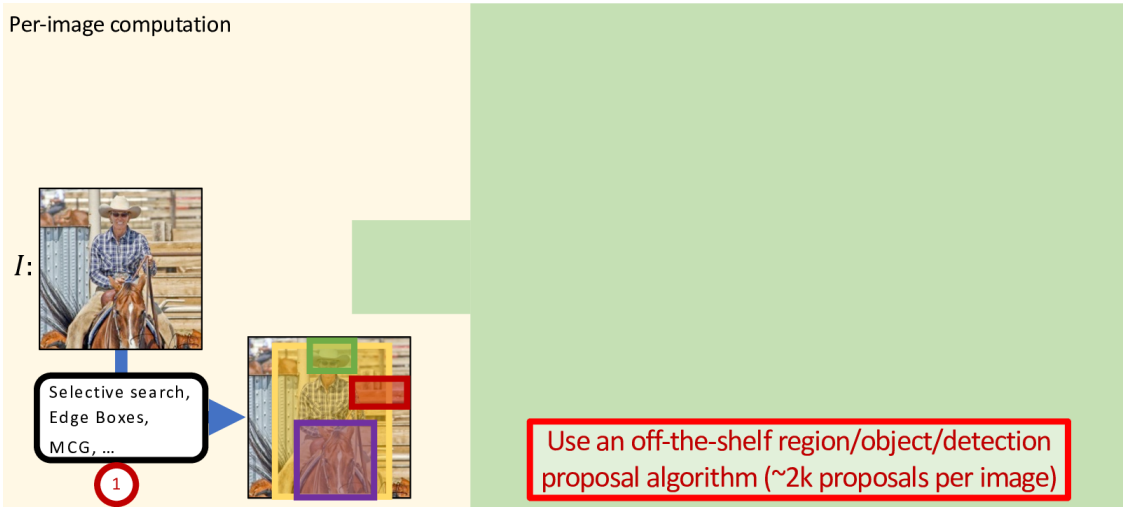
Proposal-based Object Detection



- Approximation with finite set of boxes leads to **quantization error** (quantize)
- Recover loss of localization accuracy by **regressing the location offset** (regress)
- Remove redundant predictions using non-maximum-suppression (clustering)

Girshick, Donahue, Darrell and Malik: Rich feature hierarchies for accurate object detection and semantic segmentation. CVPR, 2014.

R-CNN: Region-based Convolutional Neural Network



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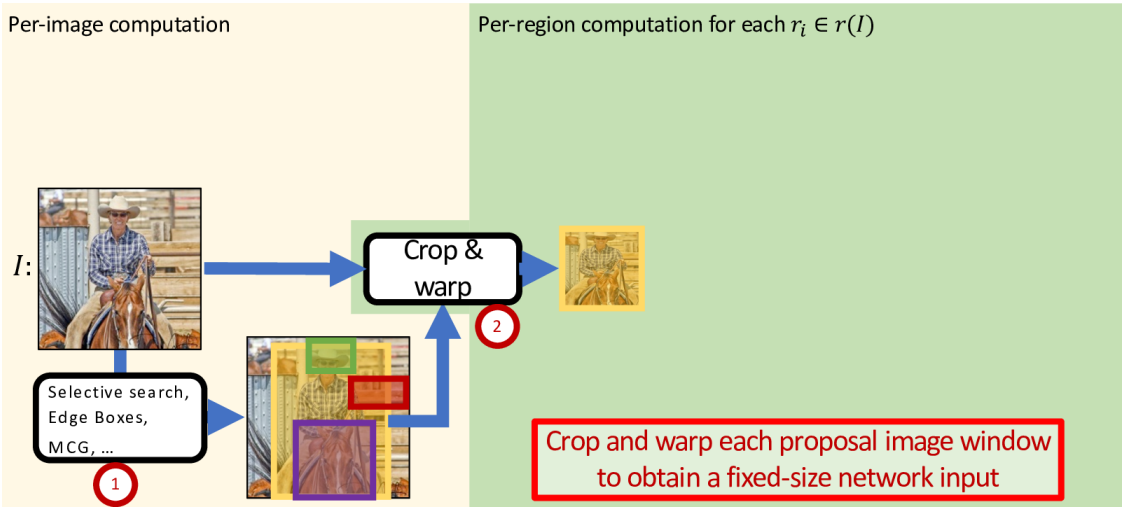
R-CNN: Region-based Convolutional Neural Network



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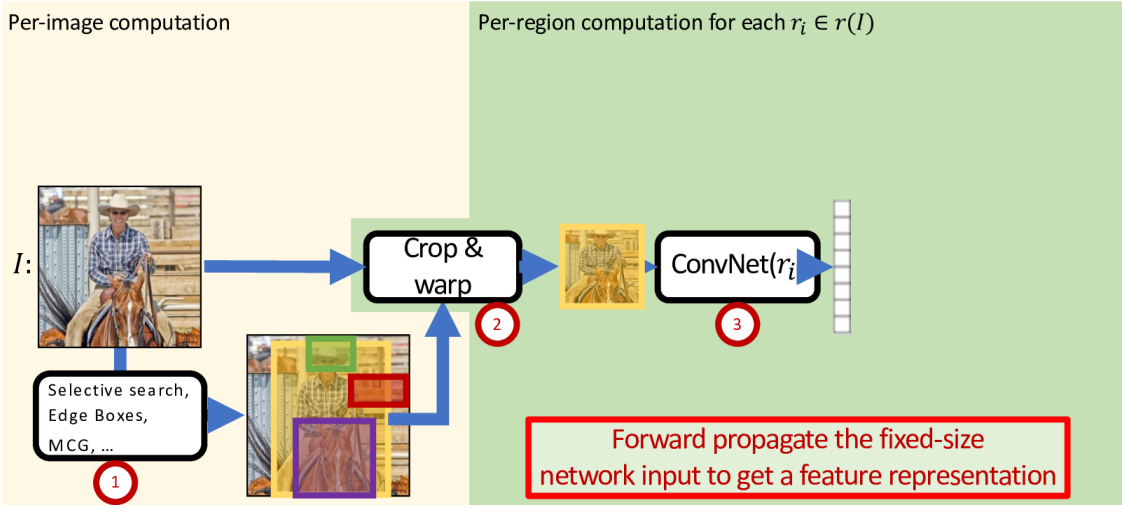

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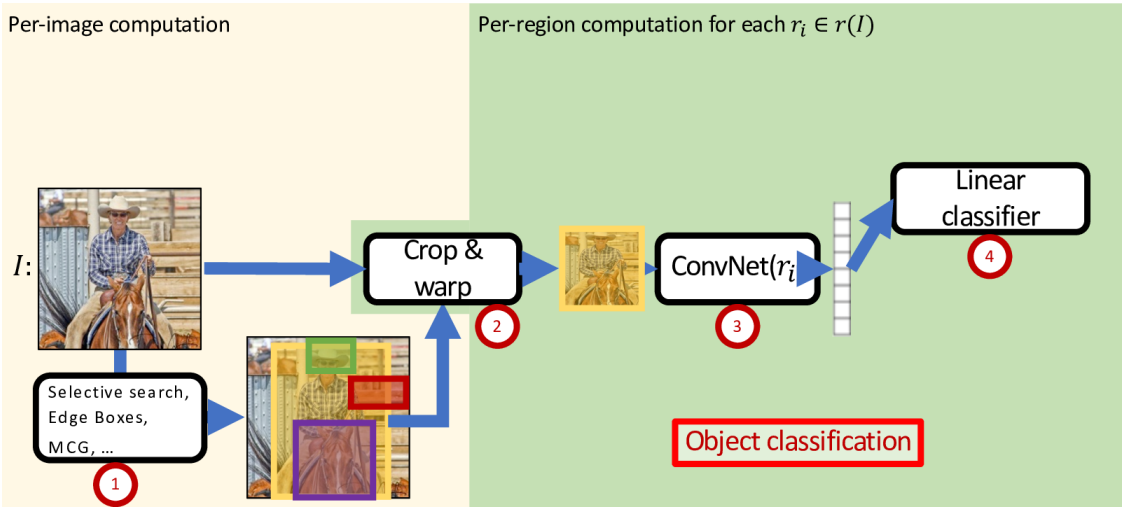

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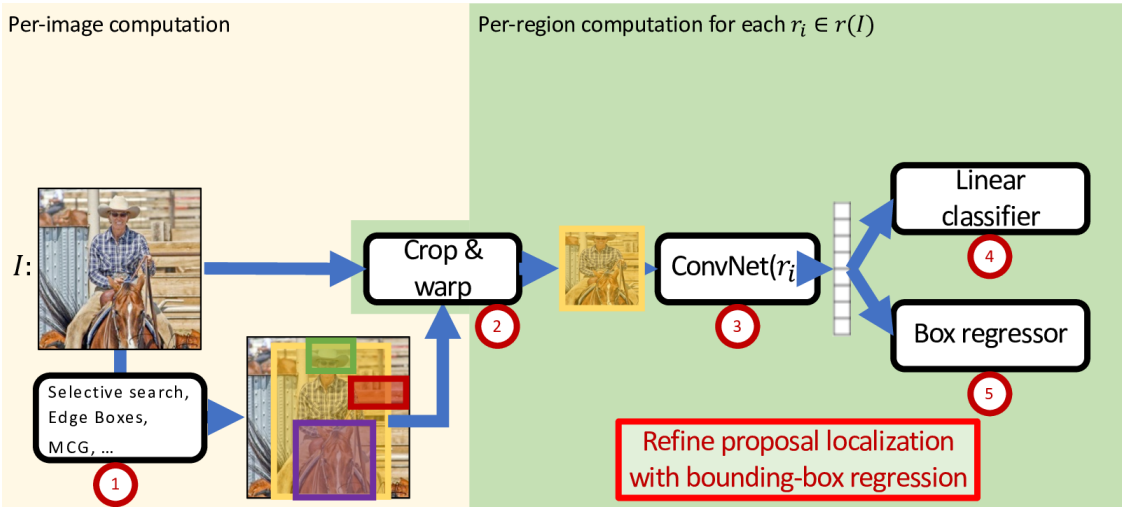

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Generalized Framework

Per-image computation

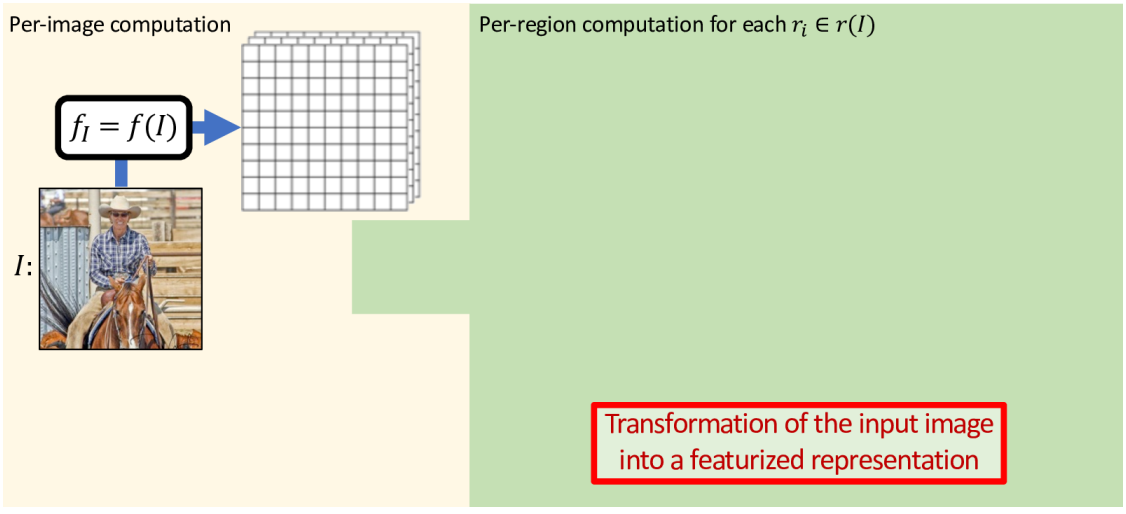
I:

Per-region computation for each $r_i \in r(I)$

Input image
per-image operations | per-region operations

Girshick, Donahue, Darrell and Malik: Rich feature hierarchies for accurate object detection and semantic segmentation. CVPR, 2014.

Generalized Framework



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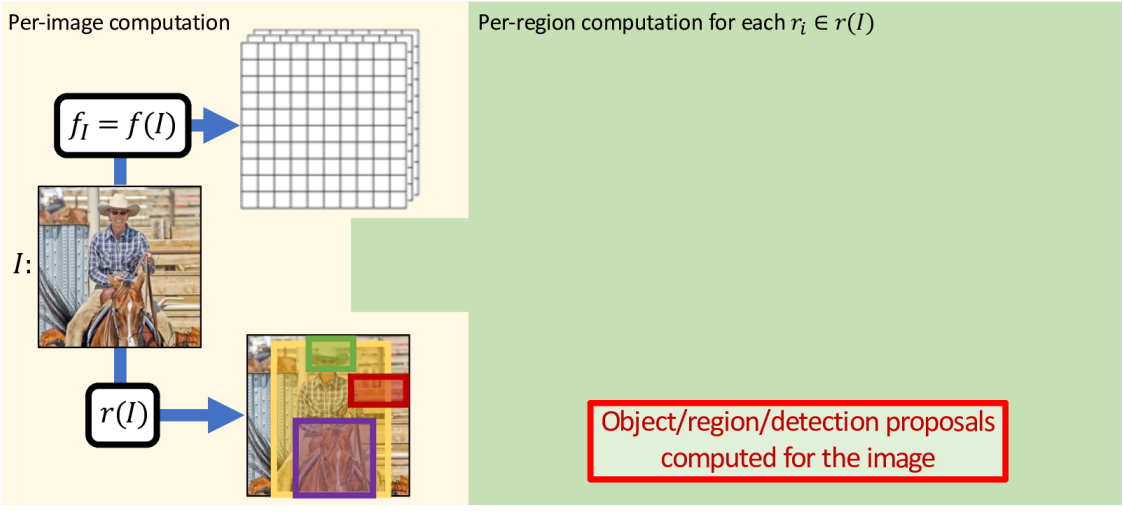
Generalized Framework



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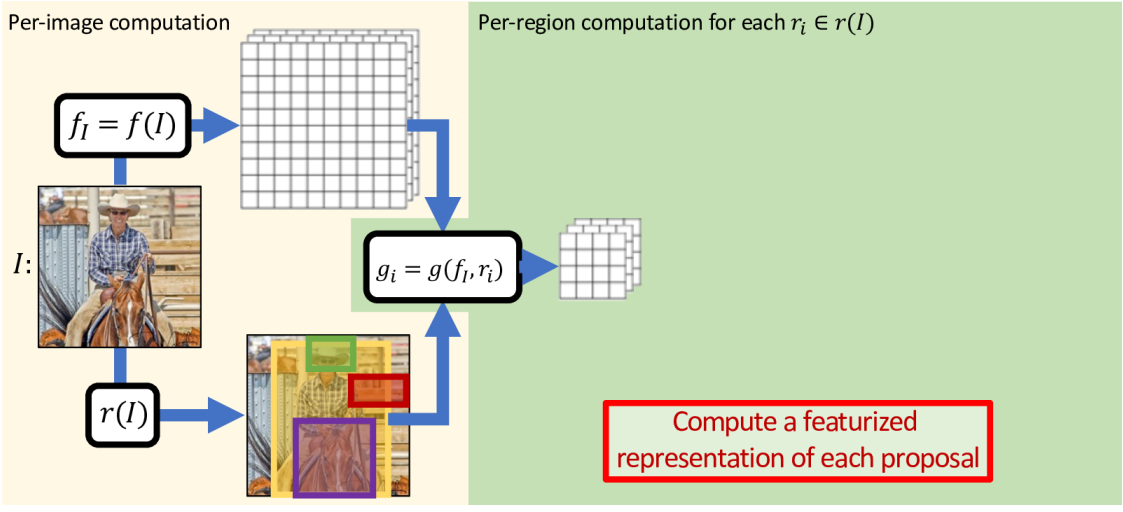
Generalized Framework



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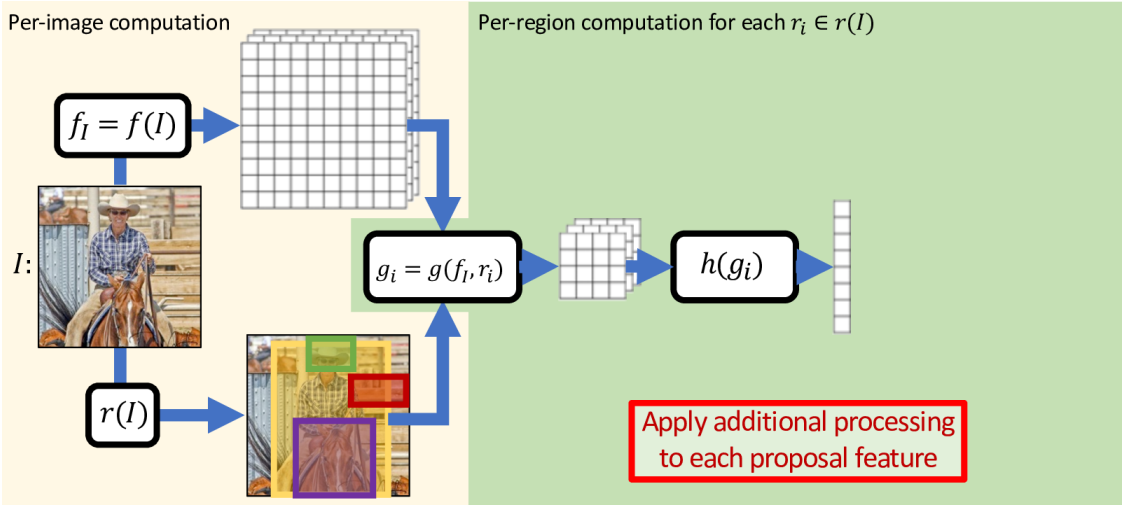

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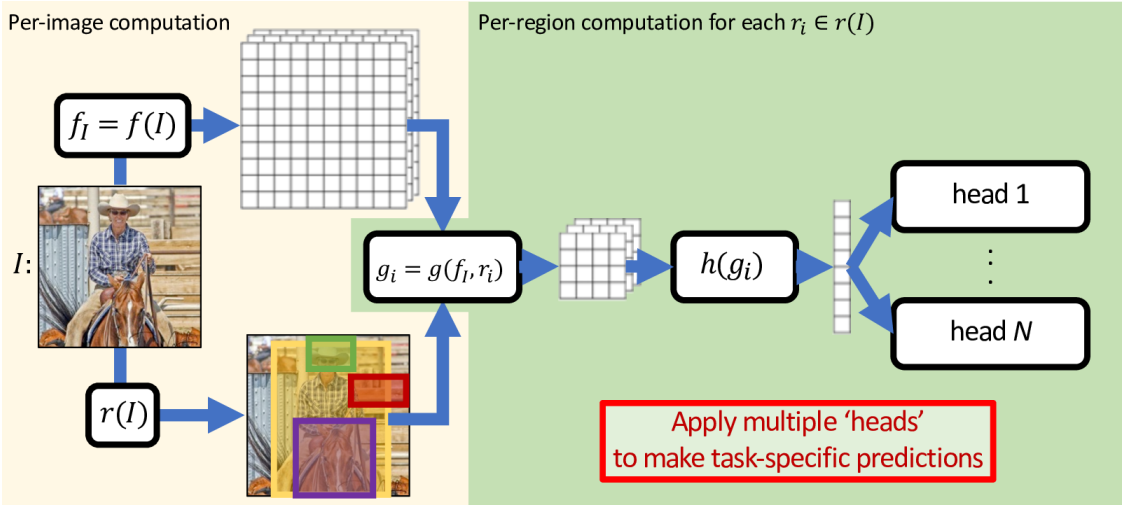
Generalized Framework



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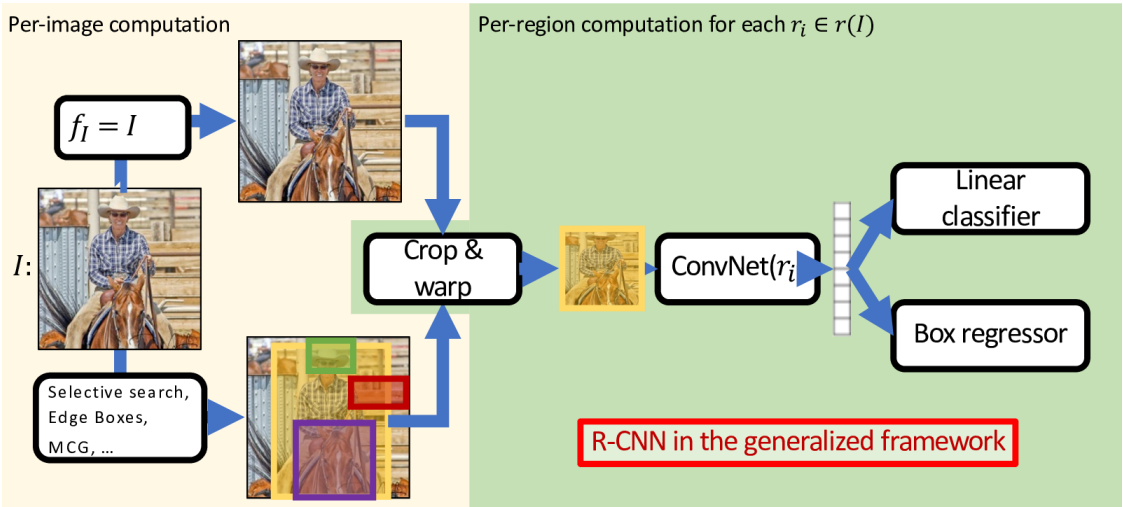
R-CNN in Generalized Framework



Girshick, Donahue, Darrell and Malik: Rich feature hierarchies for accurate object detection and semantic segmentation. CVPR, 2014.

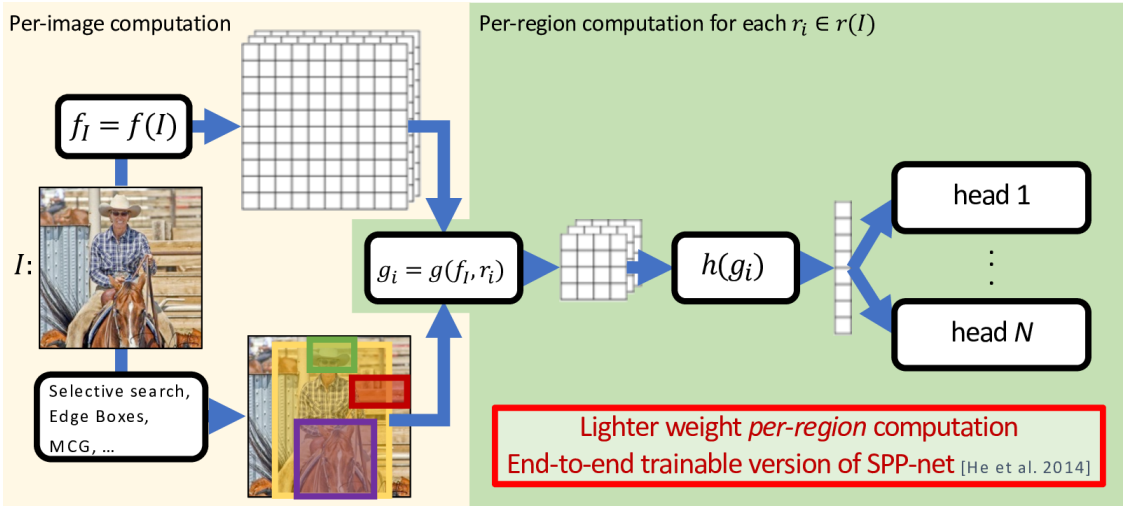
R-CNN in Generalized Framework

What is the problem with R-CNN?

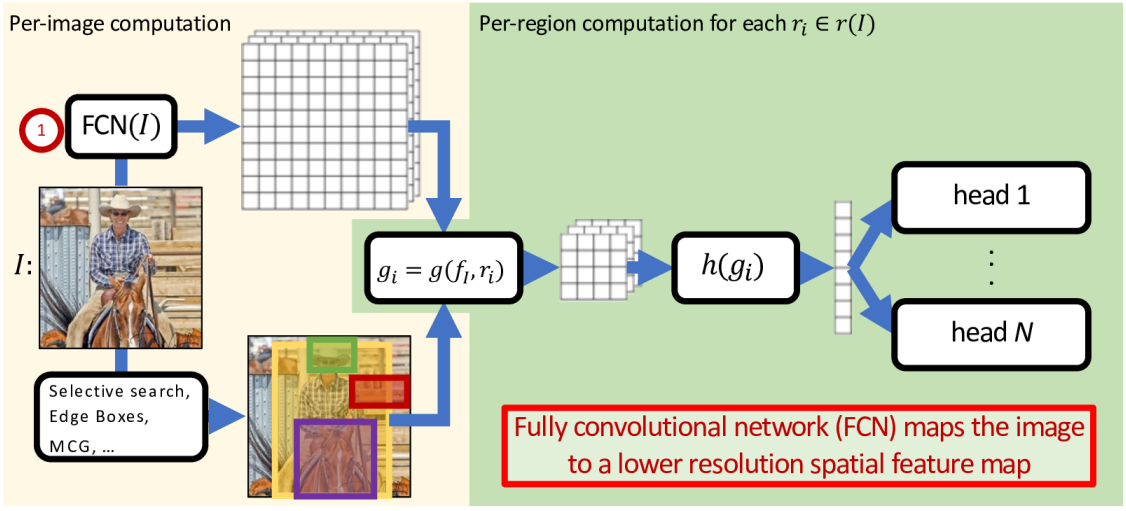
- Heavy per-region computation (e.g., 2000 full network evaluations)
- No computation/feature sharing
- Slow region proposal method adds to runtime
- Generic region proposal techniques have limited recall

Girshick, Donahue, Darrell and Malik: Rich feature hierarchies for accurate object detection and semantic segmentation. CVPR, 2014.

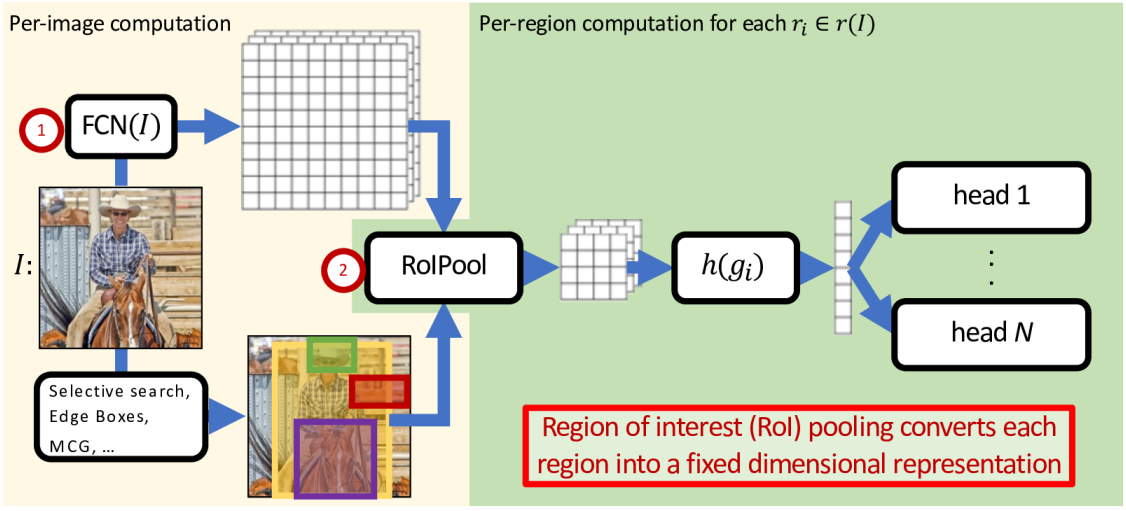
Fast R-CNN


Per-image computation
Per-region computation for each $r_i \in r(I)$
$f_I = f(I)$
I:
Selective search,
Edge Boxes,
MCG, …
$g_i = g(f_I, r_i)$
$h(g_i)$
head 1
head N
Lighter weight *per-region* computation
End-to-end trainable version of SPP-net [He et al. 2014]

Fast R-CNN

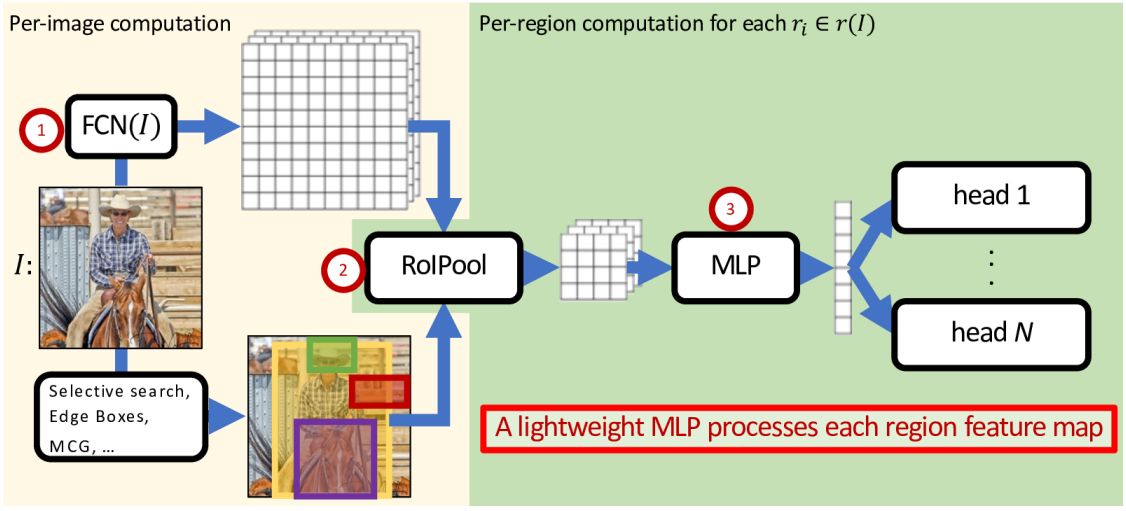

Per-image computation
Per-region computation for each $r_i \in r(I)$
1
FCN(I)
I:
Selective search,
Edge Boxes,
MCG, ...
$g_i = g(f_I, r_i)$
$h(g_i)$
head 1
head N
Fully convolutional network (FCN) maps the image
to a lower resolution spatial feature map

Fast R-CNN



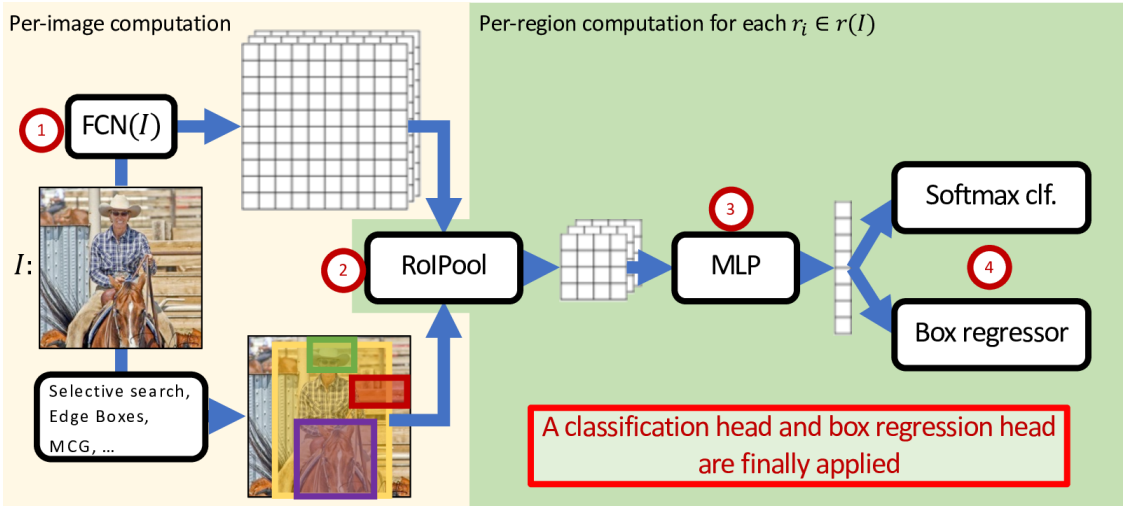
Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN



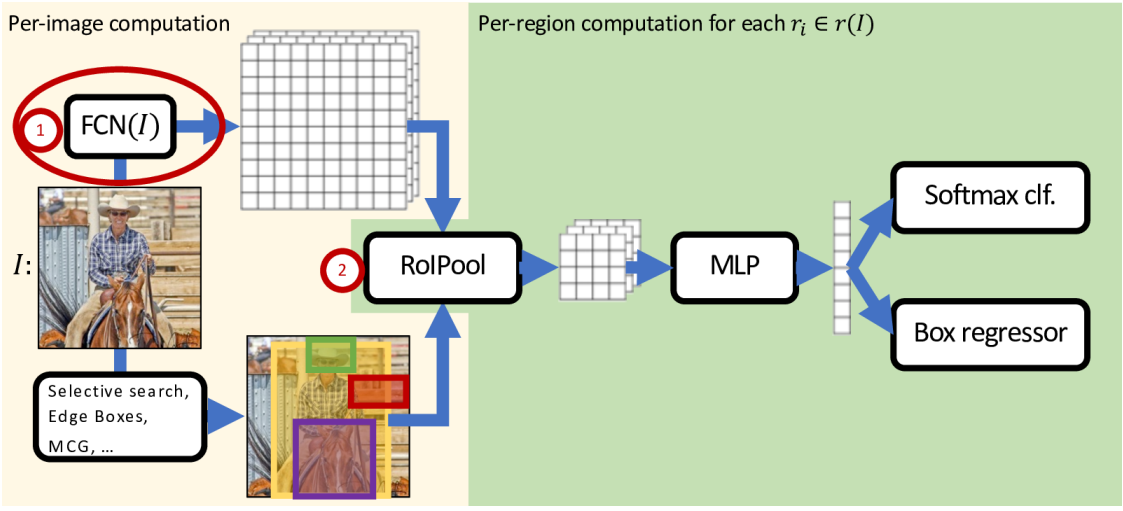
Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN



Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

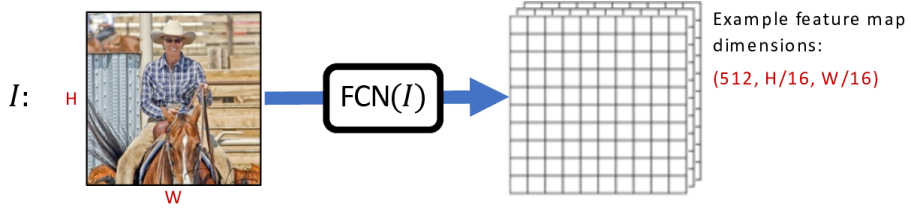


Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

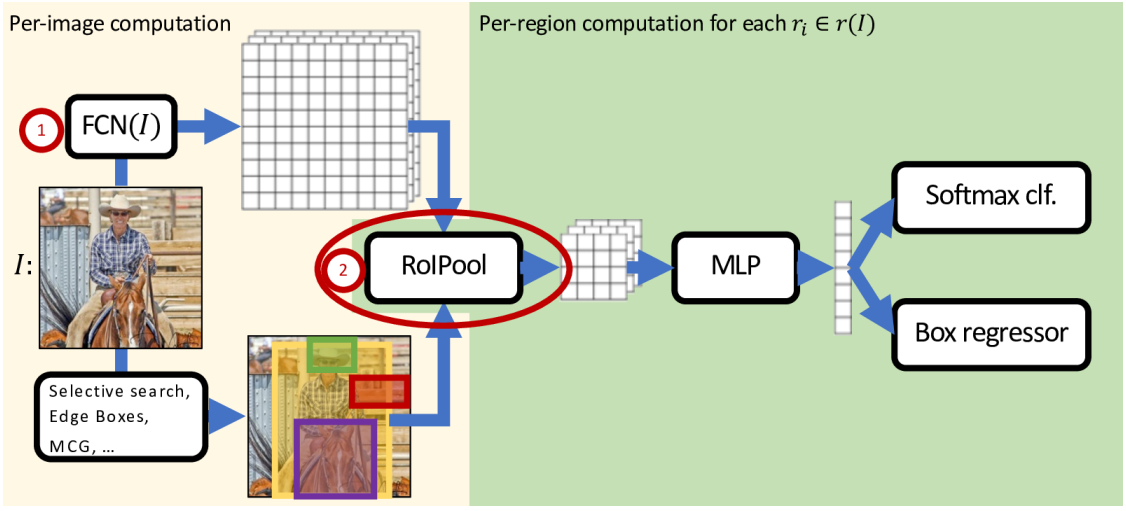
Backbone:

- Use any standard convolutional network as “backbone” architecture
  - E.g.: AlexNet, VGG, ResNet, Inception, ResNeXt, DenseNet, ...
- **Remove global pooling** $\Rightarrow$ output spatial dims proportional to input spatial dims
- A good network exploits the strongest recognition backbone (features matter!)



Girshick: Fast R-CNN. ICCV, 2015.

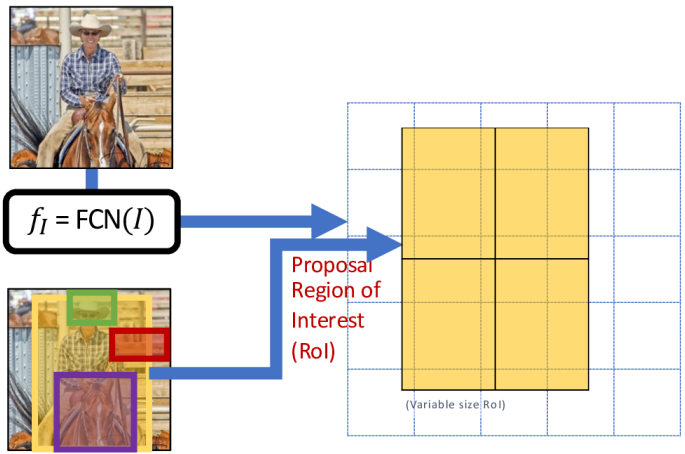
Fast R-CNN



Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

Region-of-Interest (RoI) Pooling on each Proposal:

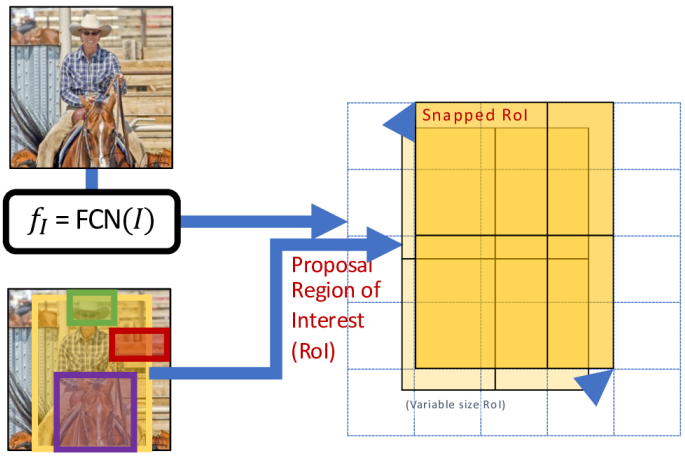


Key innovation in SPP-net [He et al. 2014]

Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

Region-of-Interest (RoI) Pooling on each Proposal:



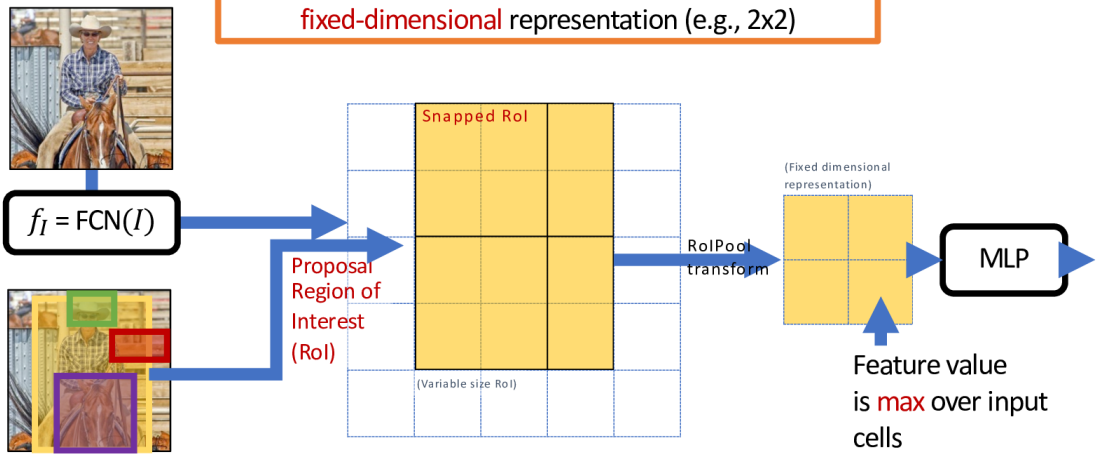
Key innovation in SPP-net [He et al. 2014]

Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

Region-of-Interest (RoI) Pooling on each Proposal:

Transform arbitrary size proposal into a fixed-dimensional representation (e.g., 2x2)



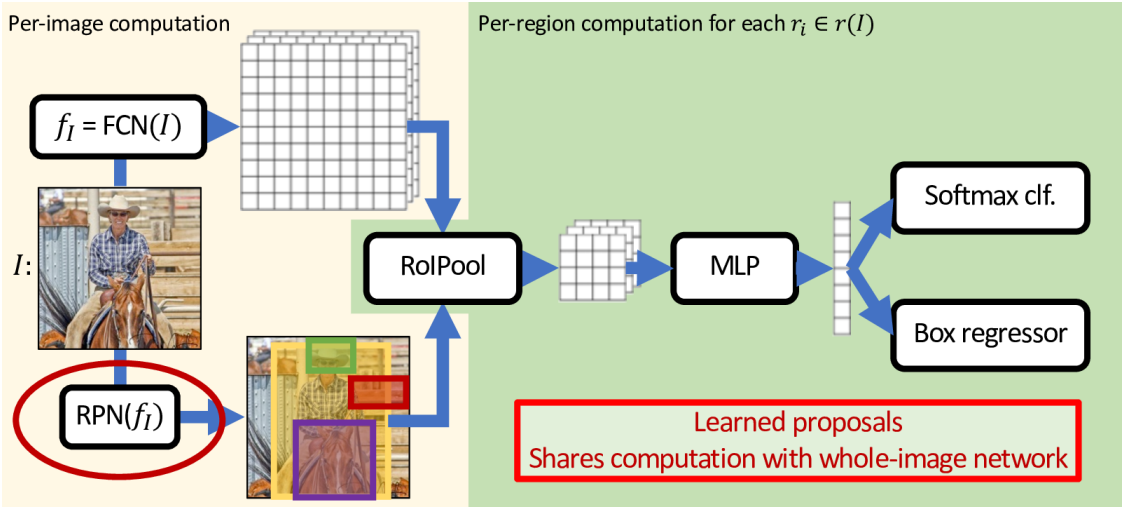
Girshick: Fast R-CNN. ICCV, 2015.

Fast R-CNN

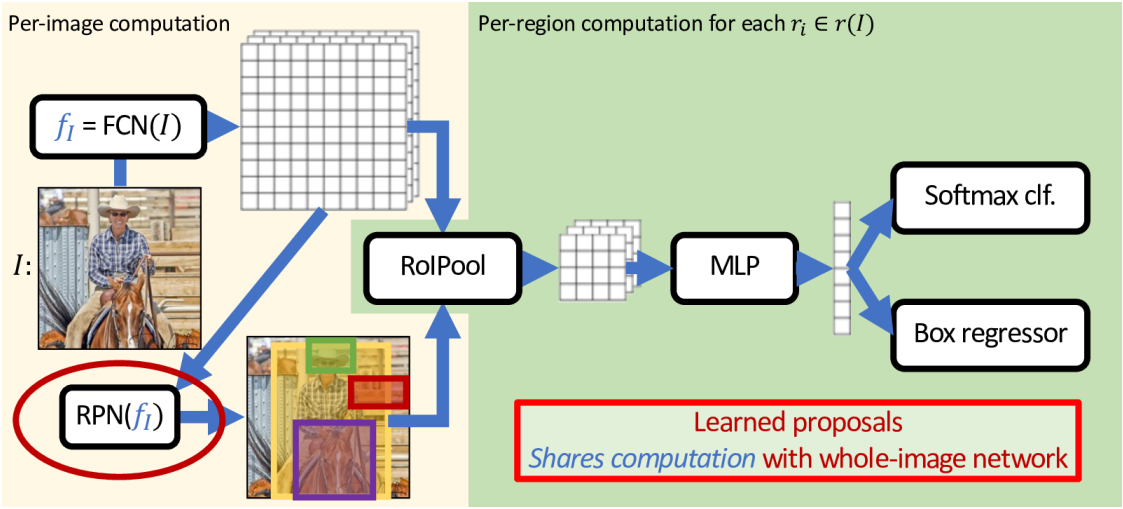
What is the problem with Fast R-CNN?

- ~~Heavy per-region computation (e.g., 2000 full network evaluations)~~
- ~~No computation/feature sharing~~
- Slow region proposal method adds to runtime
- Generic region proposal techniques have low recall

Faster R-CNN

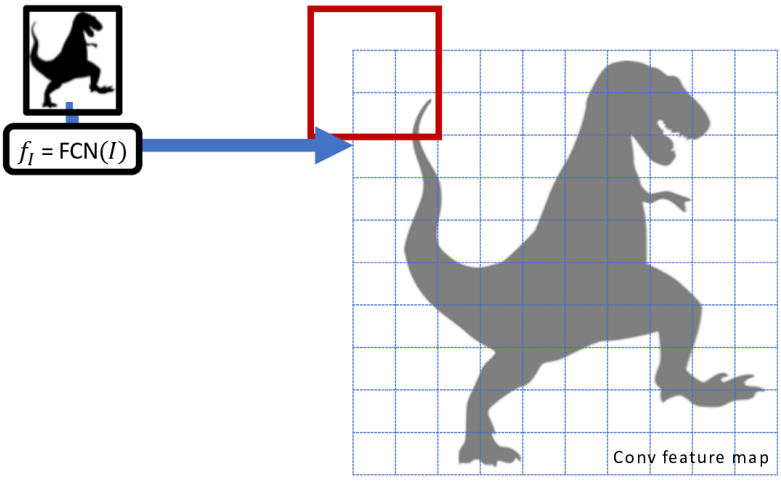

Per-image computation
Per-region computation for each $r_i \in r(I)$
f_I = FCN(I)
I:
RPN(f_I)
RoIPool
MLP
Softmax clf.
Box regressor
Learned proposals
Shares computation with whole-image network

Faster R-CNN



Ren, He, Girshick and Sun et al.: Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks. NIPS, 2015.

Faster R-CNN: Region Proposal Network (RPN)



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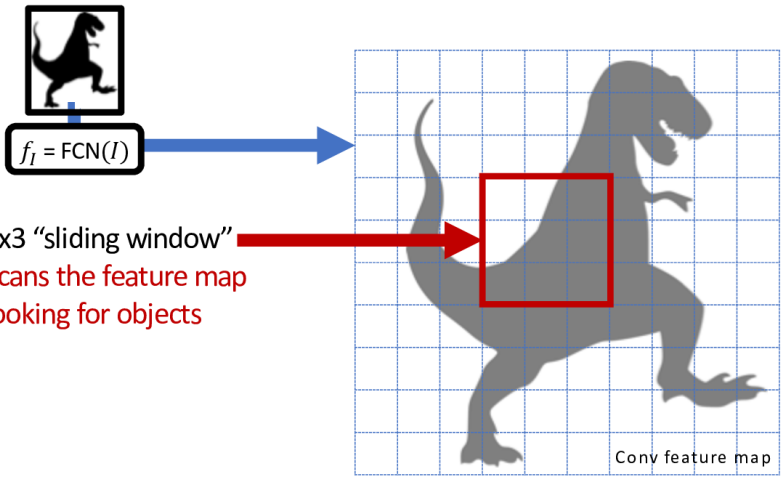
Faster R-CNN: Region Proposal Network (RPN)



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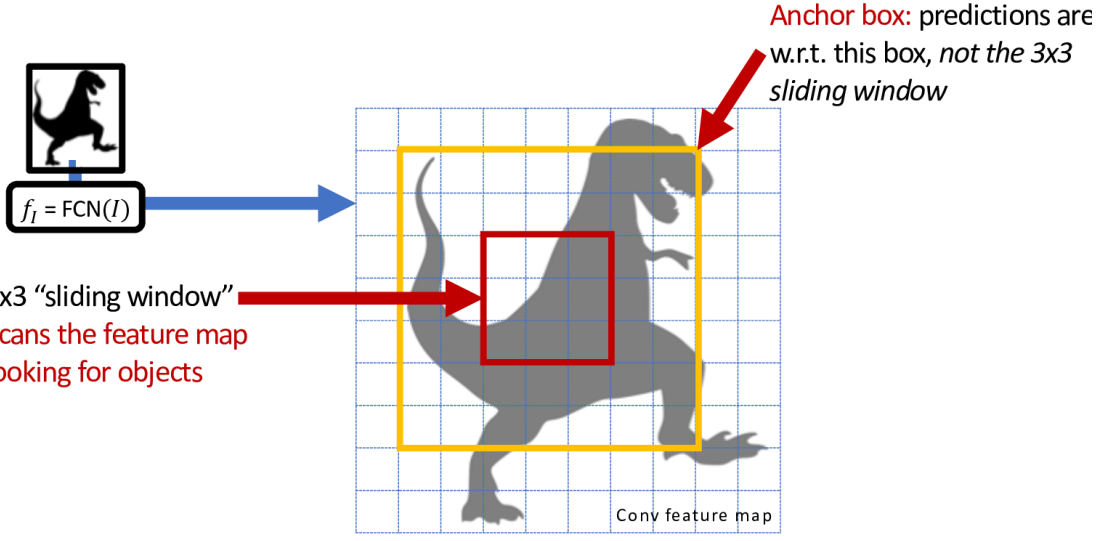
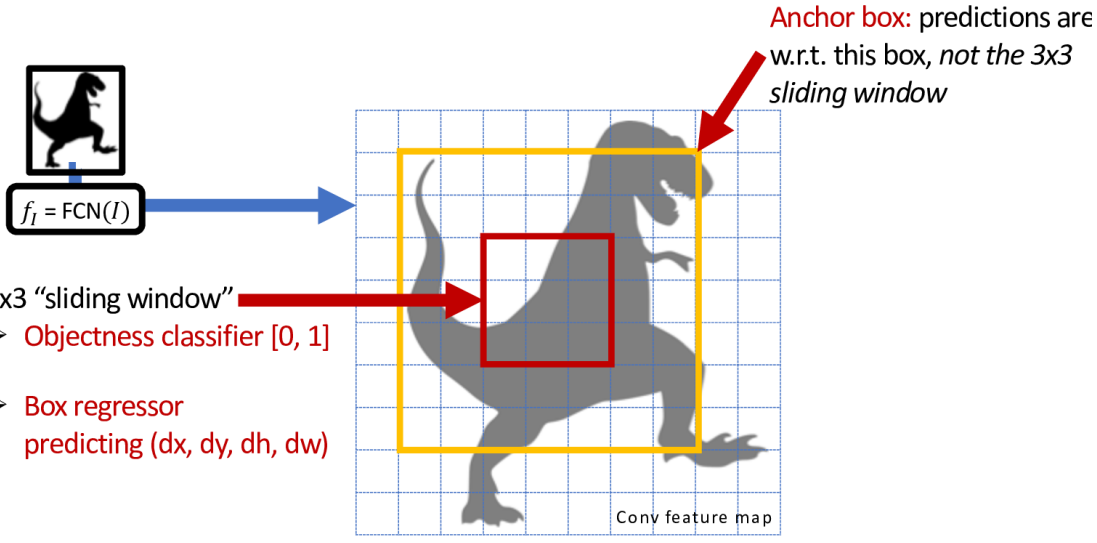
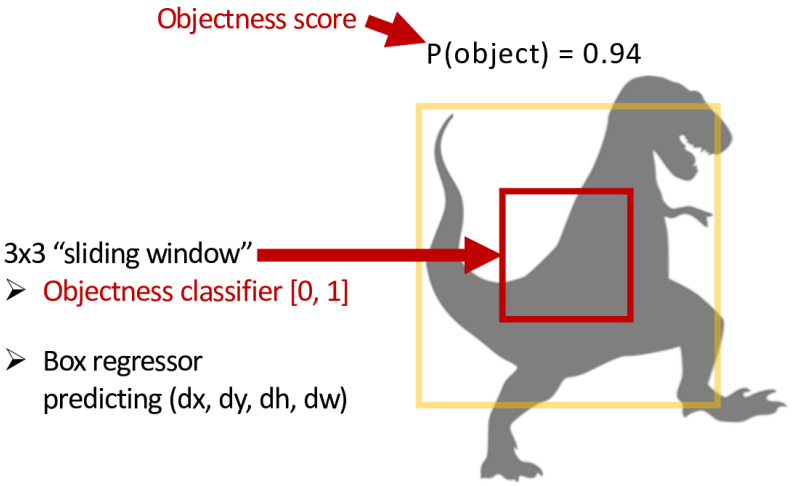
Faster R-CNN: Region Proposal Network (RPN)



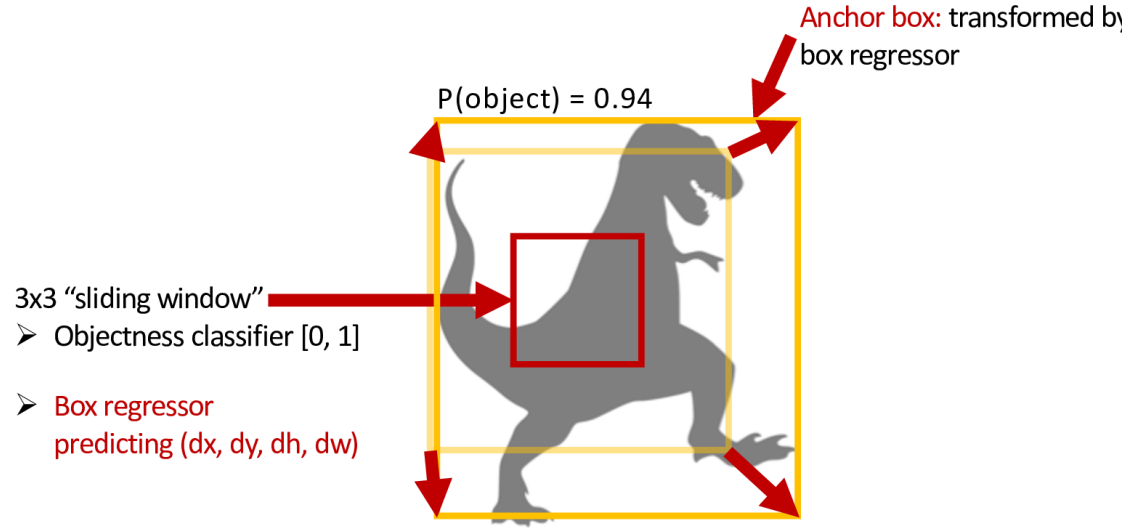
Faster R-CNN: Region Proposal Network (RPN)



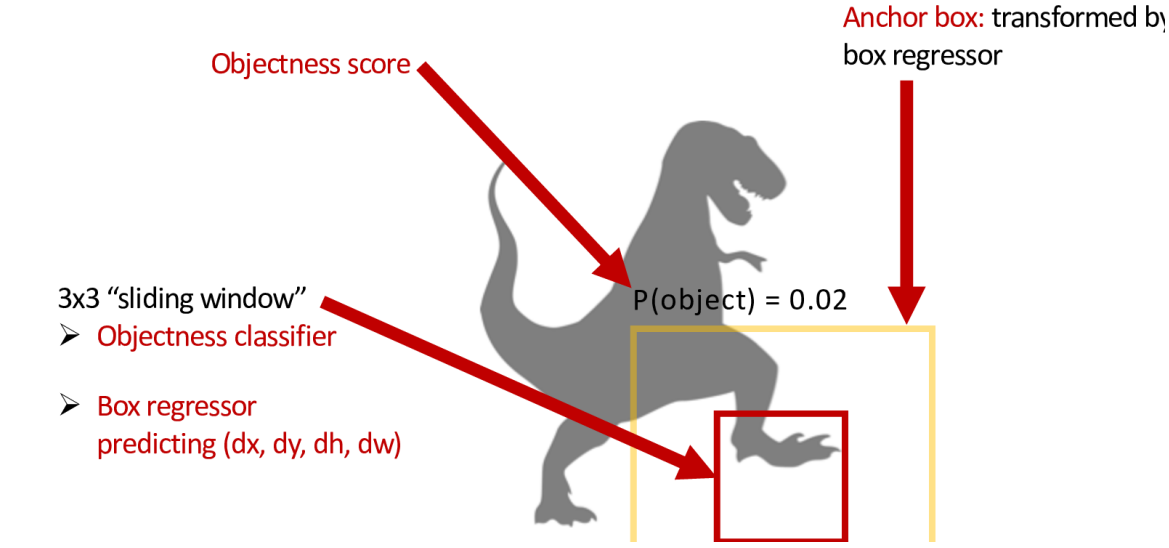
Faster R-CNN: Region Proposal Network (RPN)



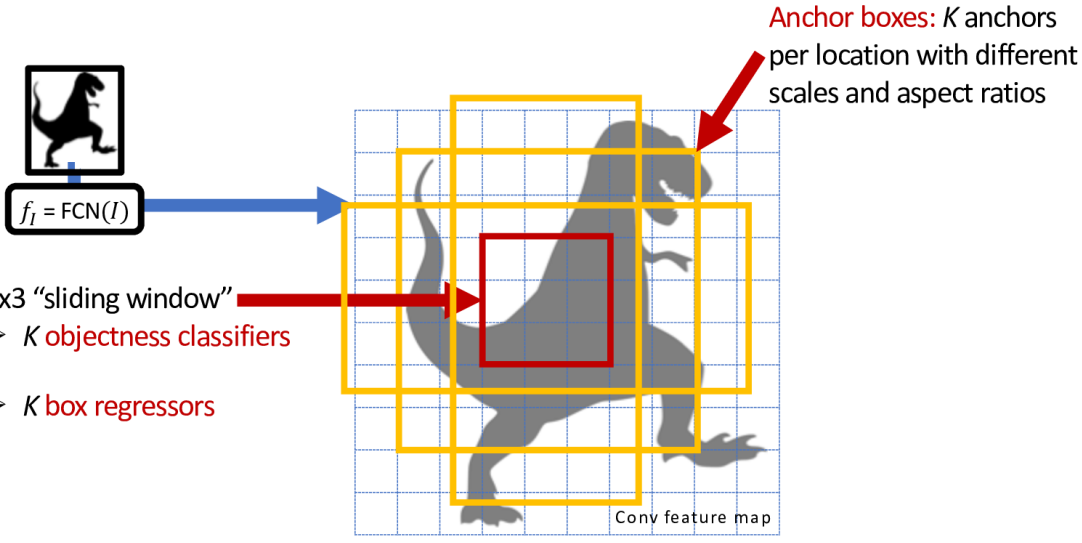
Faster R-CNN: Region Proposal Network (RPN)



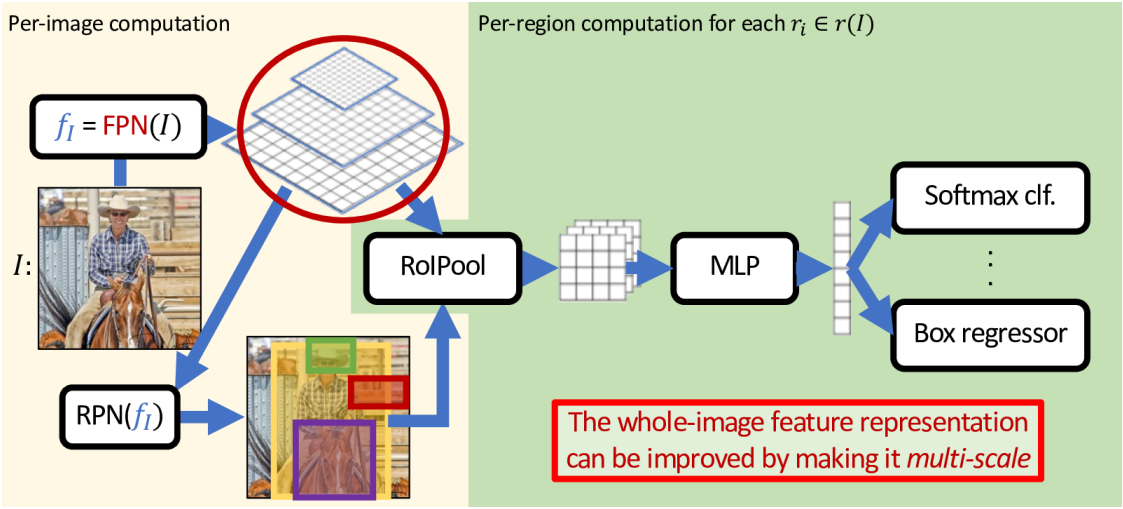
Faster R-CNN: Region Proposal Network (RPN)



Faster R-CNN: Region Proposal Network (RPN)

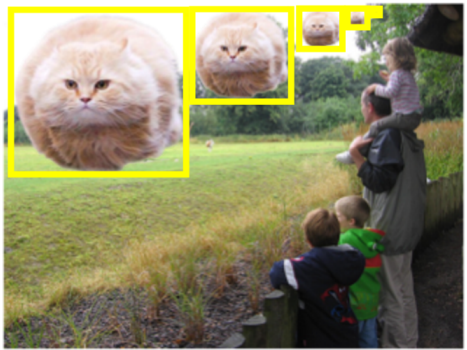


Feature Pyramid Network



Feature Pyramid Network

Goal of Feature Pyramid Network: Improve Scale Equivariance



Detectors need to

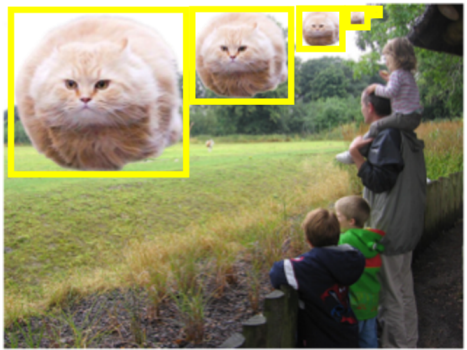
1. classify and
2. localize

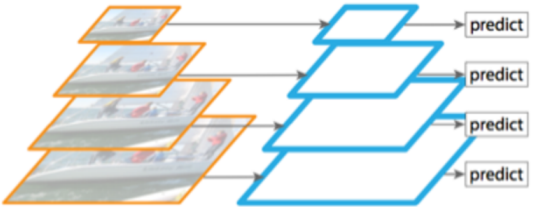
objects over a wide range of scales

FPN improves this ability

Feature Pyramid Network

Strategy 1: Image Pyramid





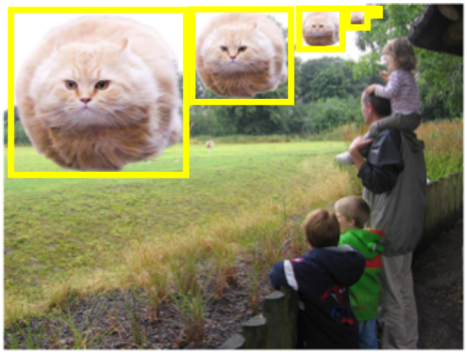
(a) Featurized image pyramid

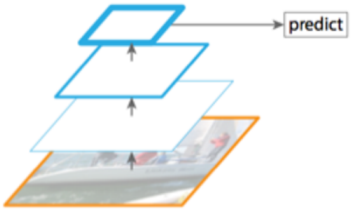
Standard solution – *slow!*

(E.g., Viola & Jones, HOG, DPM, SPP-net,

Feature Pyramid Network

Strategy 2: Multi-scale Features (Single-scale Map)





(b) Single feature map

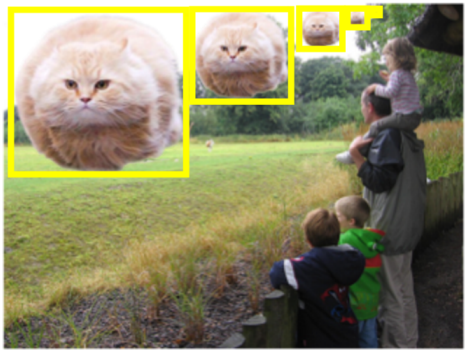
Leave it all to the features – *fast, suboptimal*

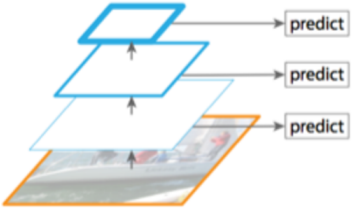
(E.g., Fast/er R-CNN, YOLO, …)

Lin, Dollár, Girshick, He, Hariharan and Belongie: Feature Pyramid Networks for Object Detection. CVPR, 2017.

Feature Pyramid Network

Strategy 3: Naïve In-network Pyramid





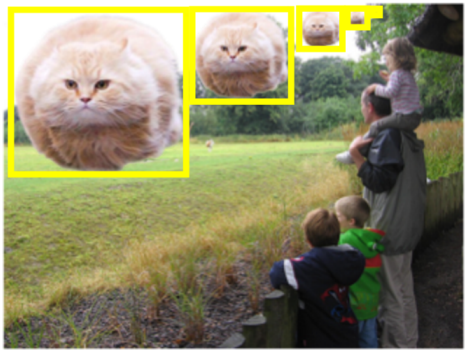
(c) Pyramidal feature hierarchy

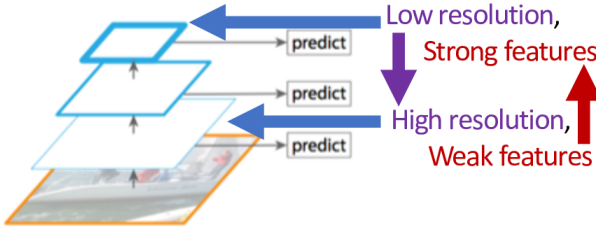
Use the internal pyramid – *fast, suboptimal*

(E.g., ≈ SSD, …)

Feature Pyramid Network

Strategy 3: Naïve In-network Pyramid





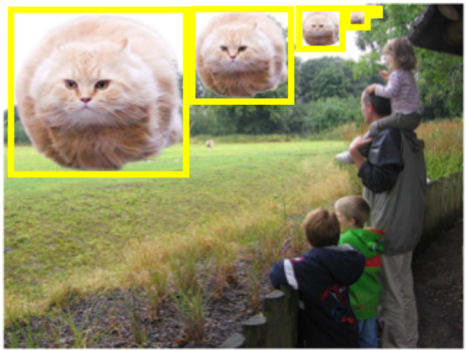
(c) Pyramidal feature hierarchy

Use the internal pyramid – *fast, suboptimal*

(E.g., ≈ SSD, …)

Feature Pyramid Network

Strategy 4: Feature Pyramid Network



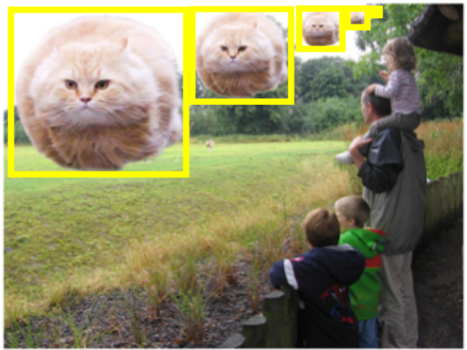
(d) Feature Pyramid Network

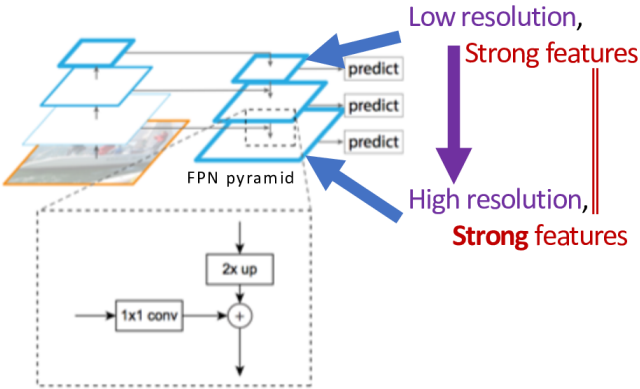
Top-down enrichment of high-res features – *fast, less suboptimal*

Lin, Dollár, Girshick, He, Hariharan and Belongie: Feature Pyramid Networks for Object Detection. CVPR, 2017.

Feature Pyramid Network

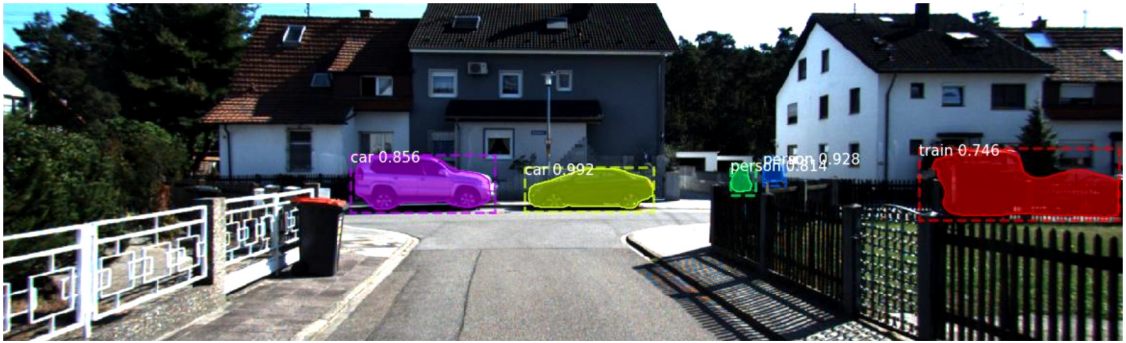
Strategy 4: Feature Pyramid Network



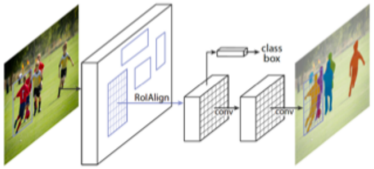


Lin, Dollár, Girshick, He, Hariharan and Belongie: Feature Pyramid Networks for Object Detection. CVPR, 2017.

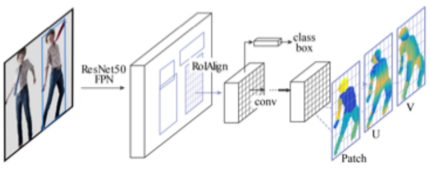
Results



Generalization to other Output Modalities



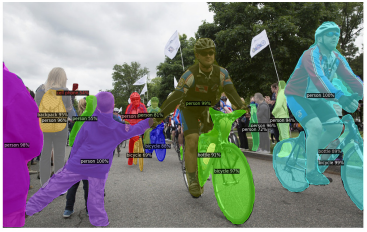
Mask R-CNN
[He, Gkioxari, Dollár, Girshick]

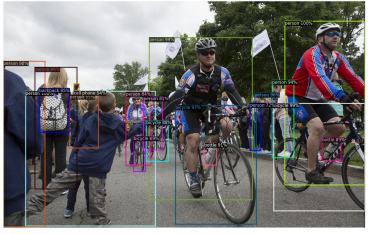


DensePose
[Güler, Neverova, Kokkinos]

- It is easy to add more/other output heads to this framework
  - Mask R-CNN: Predicting an instance segmentation mask per detection
  - DensePose: Predict object coordinates (relative 3D location on body)
  - Mesh R-CNN: Predict triangular mesh per object

Detectron2 for PyTorch



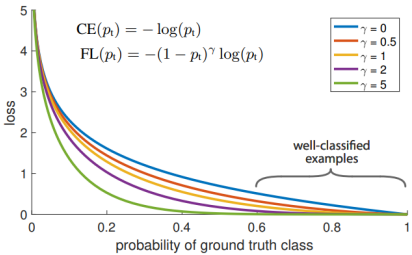


https://github.com/facebookresearch/detectron2

Foreground-Background Imbalance

Problem:

- Number of pos/neg boxes heavily imbalanced
- Before quantization: infinite imbalance
- After quantization: 0.01-0.1% foreground boxes
- Learning from imbalanced data is difficult
- Ignoring minority class $\Rightarrow$ ~100% accuracy

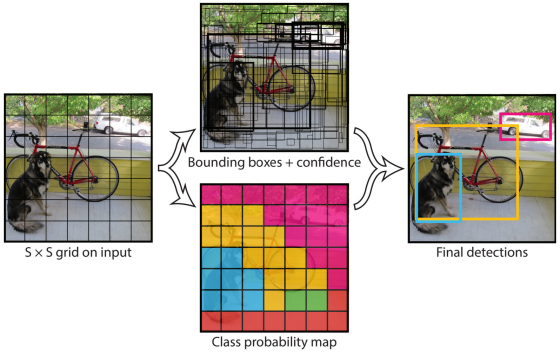


Solutions:

1. Loss function which pays attention to hard examples, e.g., Focal Loss
2. Cascades, e.g., proposal-based detectors (2nd stage sees more balanced data)
3. Quantization, e.g., single-stage detectors (imbalance small by construction)

Lin, Goyal, Girshick, He and Dollár: Focal Loss for Dense Object Detection. ICCV, 2017.

Single Stage Detection



- YOLO and SSD: Alternative to proposal-based pruning of output space
- Regress boxes and predict class probability in single stage at 7×7 locations
- Faster, but worse performance due to dramatic subsampling of output space (large quantization error hard to correct in practice $\Rightarrow$ low AP)

Joseph, Divvala, Girshick and Farhadi: You Only Look Once: Unified, Real-Time Object Detection. CVPR, 2016.

Paradigm Shift: DEtection TRansformer (DETR)

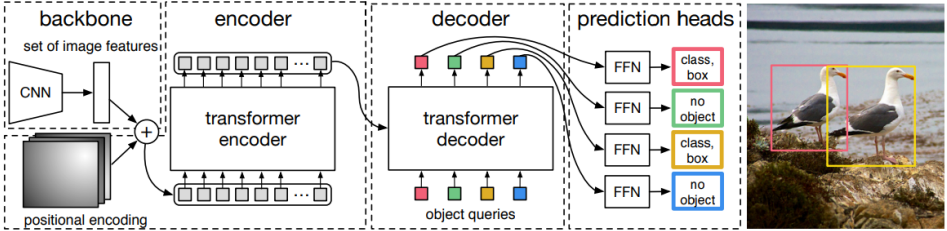
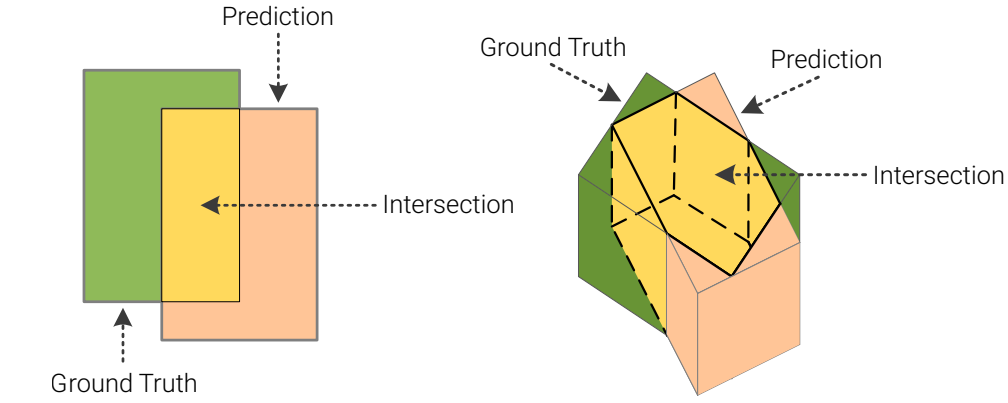


Fig. 2: DETR uses a conventional CNN backbone to learn a 2D representation of an input image. The model flattens it and supplements it with a positional encoding before passing it into a transformer encoder. A transformer decoder then takes as input a small fixed number of learned positional embeddings, which we call *object queries*, and additionally attends to the encoder output. We pass each output embedding of the decoder to a shared feed forward network (FFN) that predicts either a detection (class and bounding box) or a "`no object`" class.

Carion, Massa, Synnaeve, Usunier, Kirillov and Zagoruyko: End-to-End Object Detection with Transformers. ECCV, 2020.

10.5
3D Object Detection

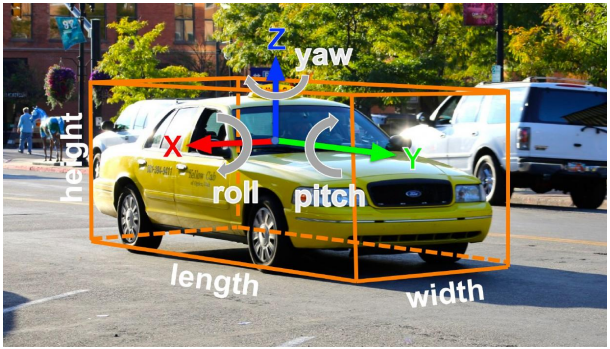
2D vs. 3D Object Detection



- Goal of 3D object detection: predict 3D bounding box for each object of interest
- Performance evaluation: 3D IoU can be calculated similarly to 2D IoU

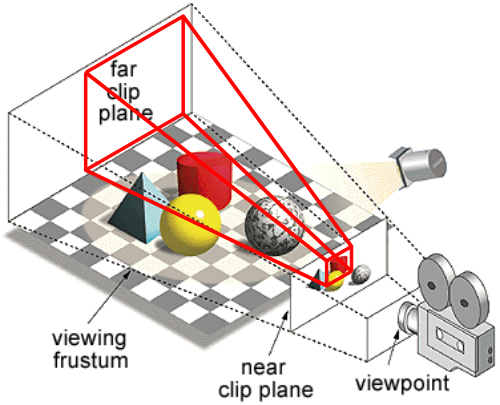
Xu et al.: 3D-GIoU: 3D Generalized Intersection over Union for Object Detection in Point Cloud. Sensors, 2019.

2D vs. 3D Bounding Box

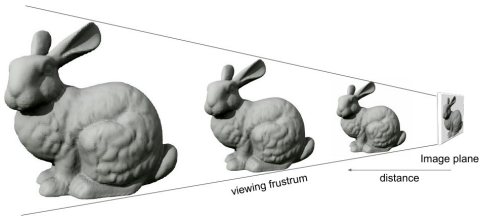


- **2D Object Detection**
  2D Box: (x, y, w, h)
- **3D Object Detection**
  3D Box: $(x, y, z, w, h, l, r, p, y)$
- **Simplification:**
  Assume zero roll and pitch
- Much harder than 2D detection
- Difficulty depends on input:
  2D image vs. 3D point cloud

Image-based 3D Object Detection

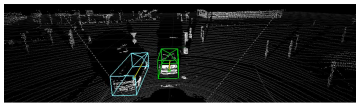


- A 2D bounding box in the image corresponds to a **frustum** in 3D
- The object can be **located anywhere** in the camera viewing frustum
- Objects of **different scales** and distances may look exactly the same:



Input Modality

Image



Lidar

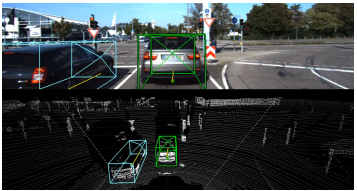


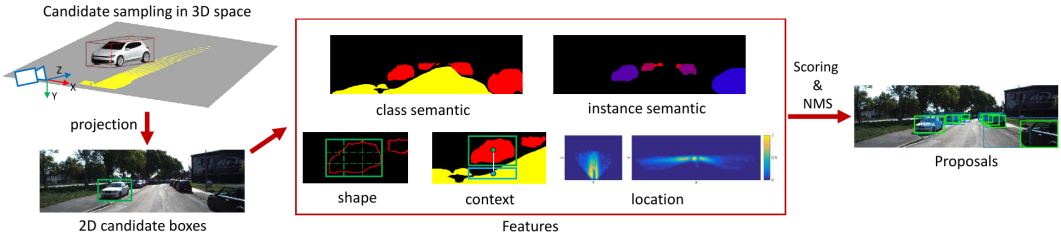
Image + Lidar

Difficulty depends on input modality:

- Regressing 3D boxes from **monocular images** requires good object size priors
- **Stereo** information helps to localize the box in 3D space (but quadratic error)
- **Lidar** sensors are sparse but provide good 3D accuracy at far range
- Several methods **combine** 2D image and Lidar information (complementary)

Image-based 3D Object Detection

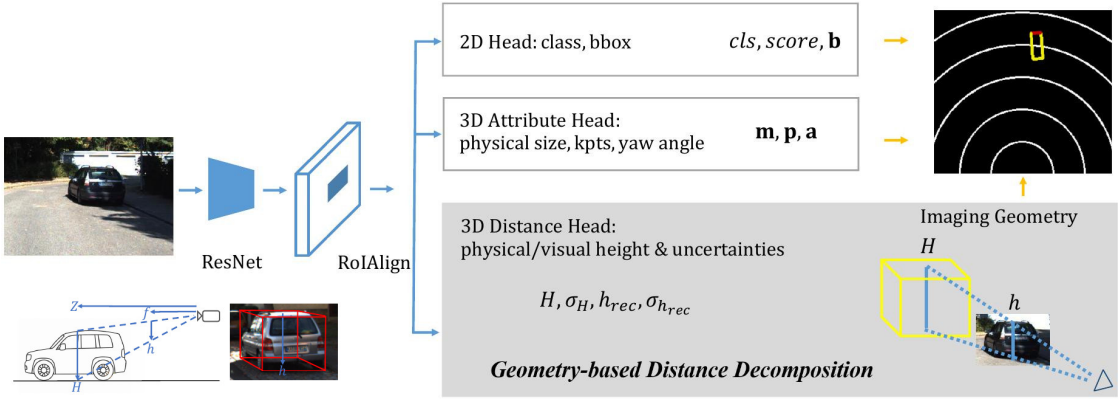
Monocular 3D Object Detection for Autonomous Driving



1. Sample **candidate 3D boxes** on the ground plane in non-road areas (gray)
2. Project 3D boxes to **image plane** in order to extract features
3. Feature-based **scoring:** semantics, instance, contour, shape, context, location
4. Final scoring and 2D refinement of top proposals using Fast R-CNN

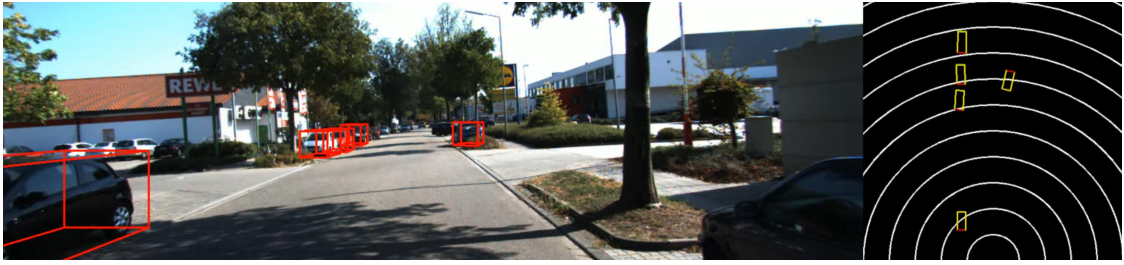
Chen, Kundu, Zhang, Ma, Fidler and Urtasun: Monocular 3D Object Detection for Autonomous Driving. CVPR, 2016.

MonoRCNN: Monocular 3D Object Detection



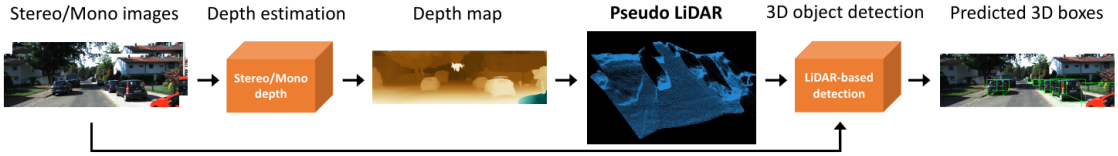
- Estimating **metrically accurate distance** is difficult from monocular images
- Idea: Regress physical and image height (+uncertainties) $\Rightarrow Z = \frac{fH}{h}$

MonoRCNN: Monocular 3D Object Detection



Shi, Ye, Chen, Chen, Chen and Kim: Geometry-based Distance Decomposition for Monocular 3D Object Detection. ICCV, 2021.

Pseudo-LiDAR: 3D Object Detection from Point Clouds

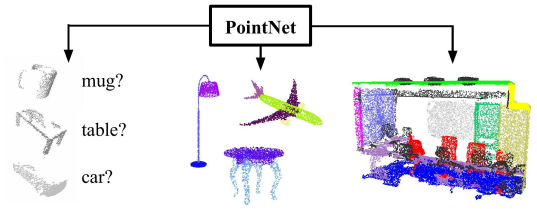


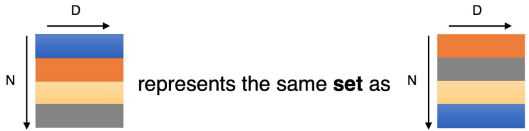
- Given stereo or monocular images, first **predict a depth map**
- Backproject the depth map into a **3D point cloud** ("pseudo-Lidar")
- Apply **standard Lidar-based detection** algorithms to this point cloud
- Performance claimed to be competitive with Lidar-based detectors
- For a recent critical discussion, refer to [Simonelle et al., ICCV 2021]

Wang, Chao, Garg, Hariharan, Campbell and Weinberger: Pseudo-LiDAR From Visual Depth Estimation. CVPR, 2019.

Lidar-based 3D Object Detection

Learning with Point Clouds





$$f(x_1, x_2, \ldots, x_n) \equiv f(x_{\pi_1}, x_{\pi_2}, \ldots, x_{\pi_n}), \quad x_i \in \mathbb{R}^D$$

Examples:

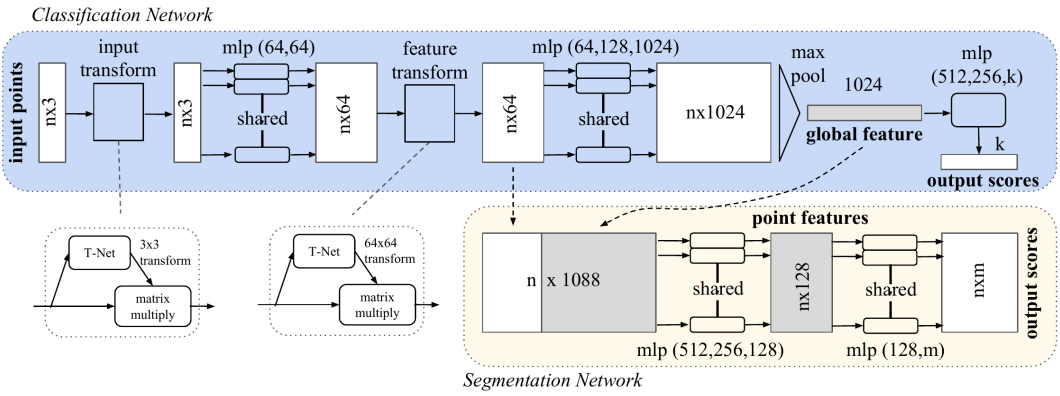
$$f(x_1, x_2, \ldots, x_n) = \max\{x_1, x_2, \ldots, x_n\}$$
$$f(x_1, x_2, \ldots, x_n) = x_1 + x_2 + \ldots + x_n$$

Challenges when learning with point clouds:

- The learned model must accommodate point clouds of **arbitrary size**
- The learned model needs to be invariant to all (N!) **permutations**
- The learned model should be invariant to **rotations** of the point cloud

Slide Credits: Charles Qi

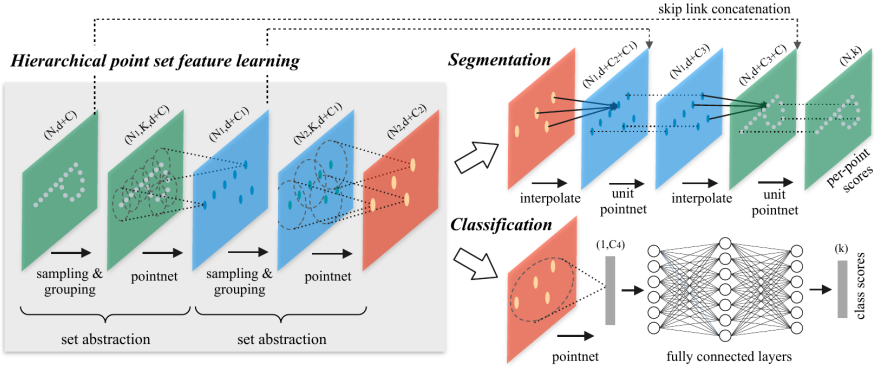
PointNet



- PointNet applies MLP per point, followed by **max-pooling** and a final (global) MLP
- Affine input/feature transformations for geometric invariance (small PointNets)

Qi, Su, Mo and Guibas: PointNet: Deep Learning on Point Sets for 3D Classification and Segmentation. CVPR, 2017.

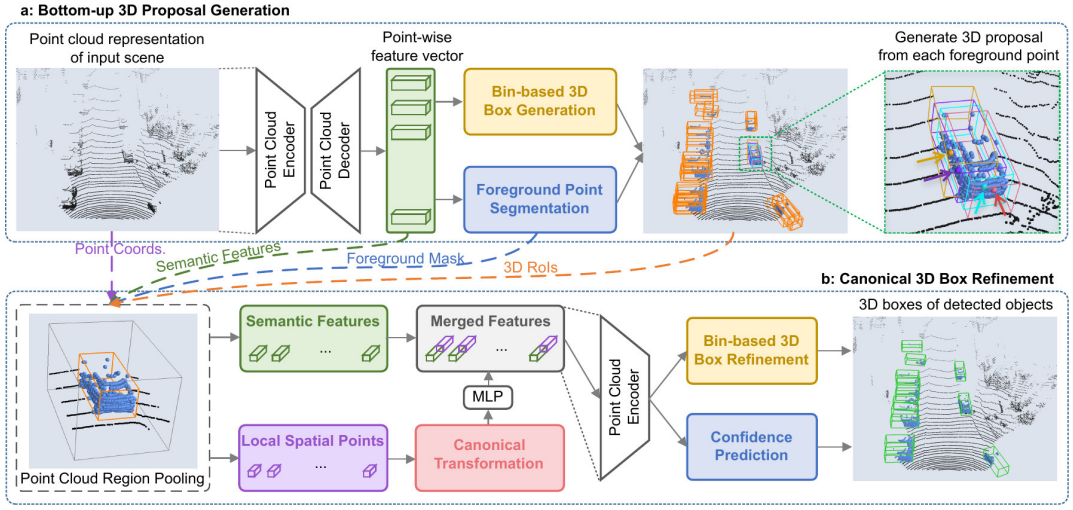
PointNet++



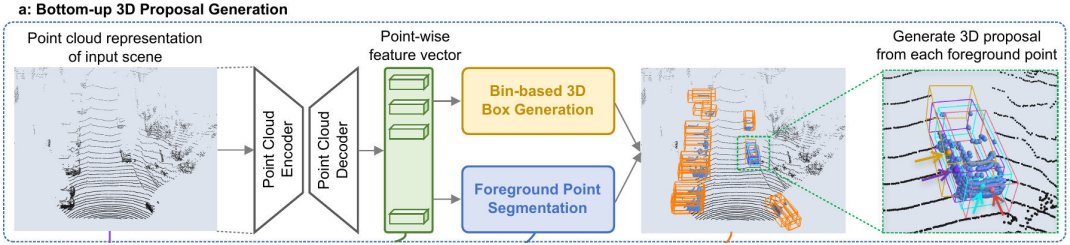
- PointNet does not capture local structures and depends on global coordinates
- PointNet++ applies PointNet **recursively** on **nested partitions** of the point set
- It learns features with increasing contextual scales ⇒ “Multi-scale PointNet”

Qi, Yi, Su and Guibas: PointNet++: Deep Hierarchical Feature Learning on Point Sets in a Metric Space. NIPS, 2017.

PointRCNN: Faster R-CNN for Point Clouds



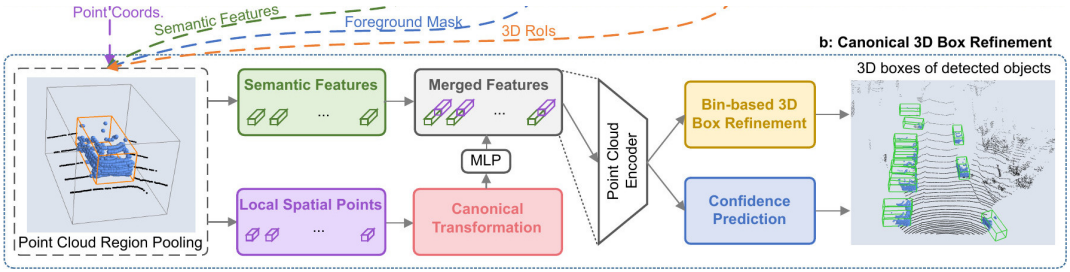
PointRCNN: Faster R-CNN for Point Clouds



1. Backbone learns discriminative point-wise features with **PointNet++**
2. **3D box proposal regression** (like Faster R-CNN) and foreground segmentation (combination of regression and classification+regression (“bin-based”) losses)
3. Pass top 100 proposals to box refinement stage

Shi, Wang and Li: PointRCNN: 3D Object Proposal Generation and Detection from Point Cloud. CVPR, 2019.

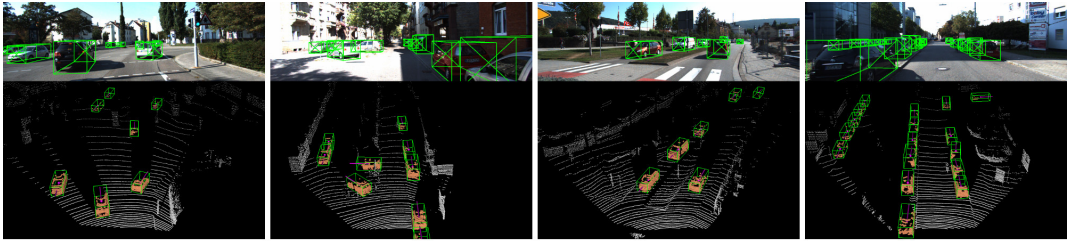
PointRCNN: Faster R-CNN for Point Clouds



1. **Pooling** of 3D point features based on 3D box proposals
2. Transform the pooled points to canonical (local) 3D box coordinates
3. **3D box refinement** by predicting residuals as in Faster R-CNN (combination of regression and classification+regression (“bin-based”) losses)

Shi, Wang and Li: PointRCNN: 3D Object Proposal Generation and Detection from Point Cloud. CVPR, 2019.

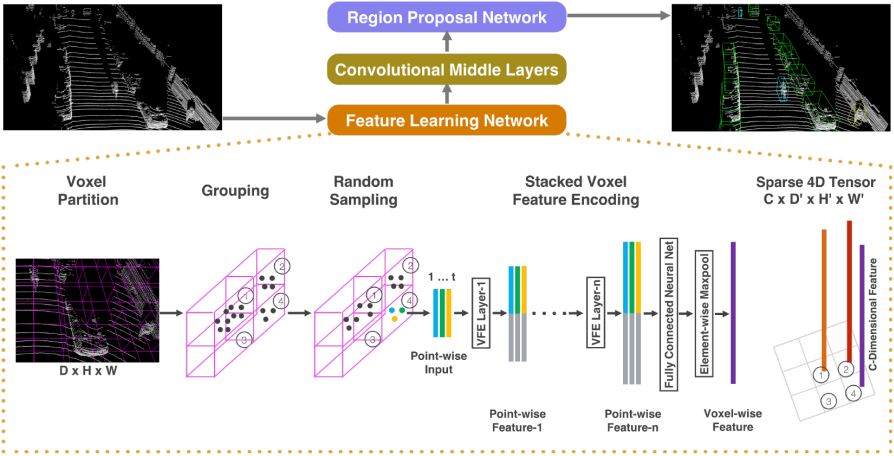
PointRCNN: Faster R-CNN for Point Clouds



Method	Modality	Car (IoU=0.7)			Pedestrian (IoU=0.5)			Cyclist (IoU=0.5)		
		Easy	Moderate	Hard	Easy	Moderate	Hard	Easy	Moderate	Hard
MV3D [4]	RGB + LiDAR	71.09	62.35	55.12	-	-	-	-	-	-
UberATG-ContFuse [17]	RGB + LiDAR	82.54	66.22	64.04	-	-	-	-	-	-
AVOD-FPN [14]	RGB + LiDAR	81.94	71.88	66.38	50.80	42.81	**40.88**	64.00	52.18	46.61
F-PointNet [25]	RGB + LiDAR	81.20	70.39	62.19	**51.21**	**44.89**	40.23	71.96	56.77	50.39
VoxelNet [43]	LiDAR	77.47	65.11	57.73	39.48	33.69	31.51	61.22	48.36	44.37
SECOND [40]	LiDAR	83.13	73.66	66.20	51.07	42.56	37.29	70.51	53.85	46.90
Ours	LiDAR	**85.94**	**75.76**	**68.32**	49.43	41.78	38.63	**73.93**	**59.60**	**53.59**

- Outperforms multi-modal methods, except for pedestrians which are small

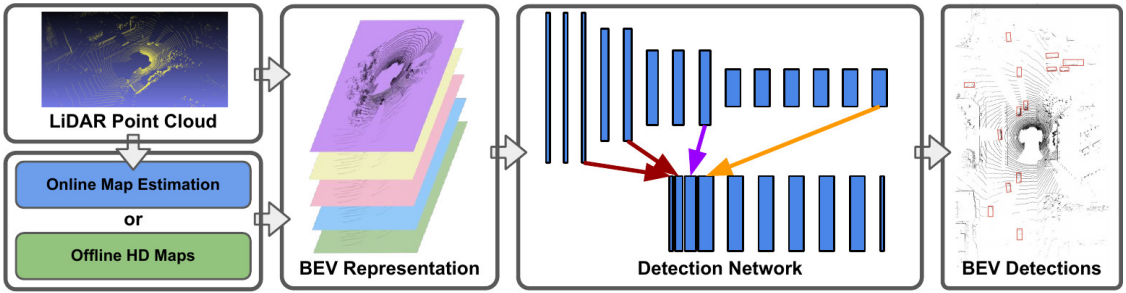
VoxelNet: Single Stage Detection with 3D Convolutions



- Alternative: Encode points into **voxel representation** and use 3D convolutions

Zhou, Tuzel: VoxelNet: End-to-End Learning for Point Cloud Based 3D Object Detection. CVPR, 2018.

PIXOR/HDNet: 2D BEV Representation

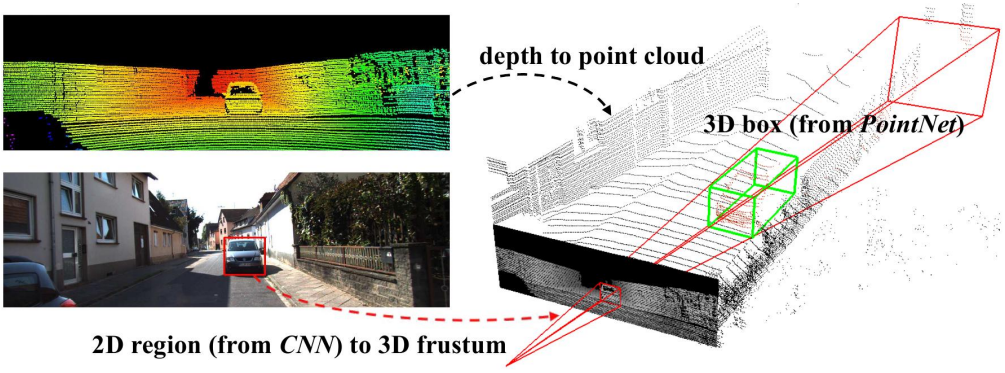


- Representation of Lidar and map data in **2D BEV**
- **Z-dimension** treated as **feature channel** ⇒ efficient 2D convolutions
- Road maps (HD maps) provide strong priors that can boost 3D detectors

Yang, Liang and Urtasun: HDNET: Exploiting HD Maps for 3D Object Detection. CoRL, 2018.

Multi-modal 3D Object Detection

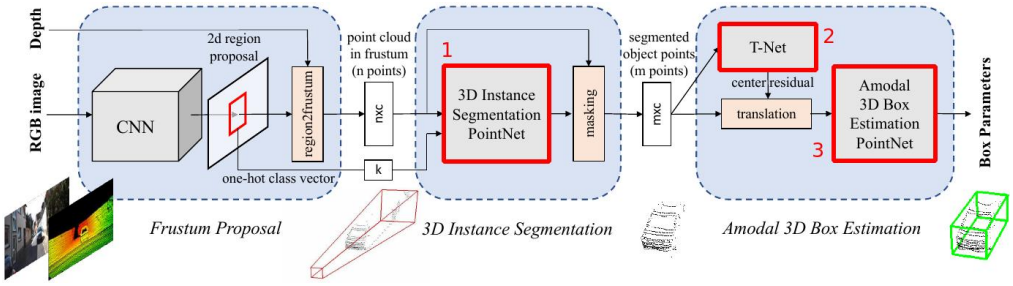
Frustum PointNet: Detect 3D Boxes in Object Frustum



1. Generate **2D object proposals** in the RGB image
2. Extract point cloud from **3D object frustum**
3. **Predict 3D bounding box** from points in frustum via PointNet

Qi, Liu, Wu, Su and Guibas: Frustum PointNets for 3D Object Detection From RGB-D Data. CVPR, 2018.

Frustum PointNet

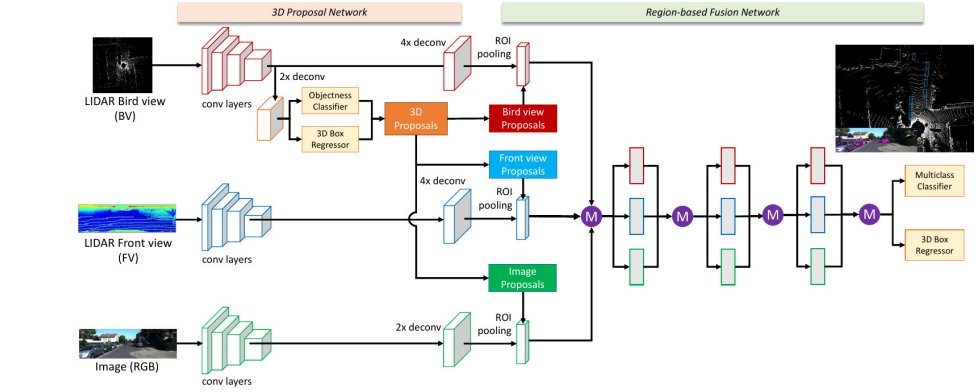


3D box prediction problem is split into **3 stages:** (all implemented via PointNets)

1. **Segmentation** of RGB point cloud (object vs. background)
2. **Translation** of points such that centroid aligns with 3D box center
3. **3D bounding box regression** (x, y, z, w, h, l, y)

Qi, Liu, Wu, Su and Guibas: Frustum PointNets for 3D Object Detection From RGB-D Data. CVPR, 2018.

MV3D: Combining Multiple 2D Views (RGB/Lidar Projections)



1. Generate 3D proposals from Lidar BV and project into **3 modalities** (Proposals)
2. **Fuse ROI-pooled features** from all modalities, regress box residuals (Refinement)

Chen, Ma, Wan, Li and Xia: Multi-view 3D Object Detection Network for Autonomous Driving. CVPR, 2017.

MV3D: Combining Multiple 2D Views (RGB/Lidar Projections)

Method	Data	IoU=0.25			IoU=0.5			IoU=0.7		
		Easy	Moderate	Hard	Easy	Moderate	Hard	Easy	Moderate	Hard
Mono3D [3]	Mono	62.94	48.2	42.68	25.19	18.2	15.52	2.53	2.31	2.31
3DOP [4]	Stereo	85.49	68.82	64.09	46.04	34.63	30.09	6.55	5.07	4.1
VeloFCN [16]	LIDAR	89.04	81.06	75.93	67.92	57.57	52.56	15.20	13.66	15.98
Ours (BV+FV)	LIDAR	96.03	88.85	88.39	95.19	87.65	80.11	71.19	56.60	55.30
Ours (BV+FV+RGB)	LIDAR+Mono	**96.52**	**89.56**	**88.94**	**96.02**	**89.05**	**88.38**	**71.29**	**62.68**	**56.56**

Table 2: **3D detection performance:** Average Precision (AP_{3D}) (in %) of 3D boxes on KITTI *validation* set.

Chen, Ma, Wan, Li and Xia: Multi-view 3D Object Detection Network for Autonomous Driving. CVPR, 2017.

Summary

- Localizing and recognizing objects is crucial for self-driving
- However, there are (∞) many possible boxes and number of objects unknown
- Challenges: appearance/viewpoint variation, illumination, clutter, occlusion
- Detection performance is typically measured using average precision
- Classic sliding-window detection methods use hand-crafted features
- Deep learning has boosted recognition performance by 10x in few years
- Two-stage detection methods (Faster R-CNN, Mask R-CNN) are state-of-the art
- Feature pyramid networks help detecting features at various scales
- 3D detection methods rely on RGB images, Lidar point clouds or both
- Lidar information is crucial for accurate 3D localization