

detection_utils.utils.ops.filter
_groundtruth_with_crowd_boxes

detection_utils.utils.ops.filter
_groundtruth_with_nan_box_coordinates

detection_utils.utils.ops.filter
_unrecognized_classes

detection_utils.utils.ops.retain
_groundtruth_with_positive_classes

detection_utils.utils.ops.retain
_groundtruth

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graph LR; A[detection_utils.utils.ops.filter_groundtruth_with_crowd_boxes] --> D[detection_utils.utils.ops.retain_groundtruth]; B[detection_utils.utils.ops.filter_groundtruth_with_nan_box_coordinates] --> D; C[detection_utils.utils.ops.filter_unrecognized_classes] --> D; E[detection_utils.utils.ops.retain_groundtruth_with_positive_classes] --> D;
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