



TUGAS AKHIR - EC184801

OPTIMISASI PENDETEKSIAN OBJEK KECIL YOLOv7 UNTUK MENDETEKSI OBJEK-OBJEK AIRBORNE

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Surabaya

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FINAL PROJECT - EC184801

YOLOv7 SMALL OBJECT DETECTION OPTIMIZATION TO DETECT AIRBORNE OBJECTS

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memperoleh gelar Sarjana Teknik pada
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YOLOv7 SMALL OBJECT DETECTION OPTIMIZATION TO DETECT AIRBORNE OBJECTS

FINAL PROJECT

Submitted to fulfill one of the requirements
for obtaining a degree Bachelor of Engineering at
Undergraduate Study Program of Computer Engineering
Department of Computer Engineering
Faculty of Faculty of Intelligent Electrical and Informatics Technology
Sepuluh Nopember Institute of Technology

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Dengan ini menyatakan bahwa Tugas Akhir dengan judul "OPTIMISASI PENDETEKSIAN OBJEK KECIL YOLOv7 UNTUK MENDETEKSI OBJEK-OBJEK AIRBORNE" adalah hasil karya sendiri, berfsifat orisinal, dan ditulis dengan mengikuti kaidah penulisan ilmiah.

Bilamana di kemudian hari ditemukan ketidaksesuaian dengan pernyataan ini, maka saya bersedia menerima sanksi sesuai dengan ketentuan yang berlaku di Institut Teknologi Sepuluh Nopember.

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Hereby declared that the Final Project with the title of "*YOLOv7 SMALL OBJECT DETECTION OPTIMIZATION TO DETECT AIRBORNE OBJECTS*" is the result of my own work, is original, and is written by following the rules of scientific writing.

If in future there is a discrepancy with this statement, then I am willing to accept sanctions in accordance with provisions that apply at Sepuluh Nopember Institute of Technology.

Surabaya, July 2023

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ABSTRAK

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Judul Tugas Akhir : OPTIMISASI PENDETEKSIAN OBJEK KECIL YOLOv7 UNTUK MENDETEKSI OBJEK-OBJEK AIRBORNE
Pembimbing : 1. Reza Fuad Rachmadi, S.T., M.T., Ph.D
 2. Dr. I Ketut Eddy Purnama, S.T., M.T.

Pada penelitian ini, kami menunjukkan percobaan kami untuk meningkatkan kemampuan deteksi YOLOv7 terhadap objek *airborne*. Objek-objek di *airborne* tampak sangat kecil pada gambar kamera ketika berada dalam jarak yang jauh. Namun, karena kecepatan pergerakan objek *airborne* itu tinggi, penting untuk mendeteksinya saat masih berada dalam jarak yang jauh. Oleh karena itu, YOLOv7 perlu dioptimalkan untuk dapat mendeteksi objek-objek kecil dengan baik. Dalam penelitian ini, kami mengusulkan beberapa modifikasi yang berupa perubahan dalam arsitektur (menambahkan kepala deteksi tambahan, mengalihkan skala fitur deteksi, dan mengganti *head* YOLO dengan *decoupled anchor-free head*), penerapan teknik *bag-of-freebies* (rekalkulasi anchor dan augmentasi mosaik), serta merubah proses inferensi (mempartisi gambar dan melakukan inferensi pada setiap partisi). Melalui eksperimen yang komprehensif, kami menemukan bahwa kombinasi penggantian *head* YOLO dengan *decoupled anchor-free head* dan melakukan inferensi pada partisi-partisi menghasilkan model yang memiliki peningkatan paling signifikan pada *mean average precision* (mAP) yaitu sebesar 46,18% dan tetap mempertahankan kecepatan inferensi yang *real-time* (≥ 10 FPS). Peningkatan ini jauh lebih tinggi dibandingkan dengan YOLOv7 polos tanpa modifikasi yang hanya mampu mencapai skor mAP sebesar 0%.

Kata Kunci: *Deteksi Objek Kecil, YOLOv7, Modifikasi Arsitektur, Modifikasi Bag-of-Freebies, Objek Airborne*

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ABSTRACT

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Advisors : 1. Reza Fuad Rachmadi, S.T., M.T., Ph.D
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In this research, we present an attempt to improve the detection capability of YOLOv7 for airborne objects. Airborne objects appear considerably small in camera images when they are located at a considerable distance from the camera. However, due to their high speed of movement, it is crucial to detect them while they are still far away. Therefore, to effectively detect these objects, YOLOv7 needs to be optimized for small objects. To address this challenge, we proposed several modifications that include changes in the architecture (adding an extra detection head, modifying the feature-map source, and replacing the detection head with a detached anchor-free head), application of bag-of-freebies techniques (anchor recalculation and mosaic augmentation), and change in the inference process (partitioning the image and performing inference on each partition). Through comprehensive experimentation, we have discovered that the combination of replacing the detection head with a detached anchor-free head, and performing inference on partitions yields the most promising results, with a significant increase in mean average precision (mAP) of 46.18% while still maintaining real-time inference speed (greater than 10 FPS). This improvement is notably higher compared to the unmodified plain YOLOv7, which achieved a mAP score of 0%.

Keywords: *Small Object Detection, YOLOv7, Architecture Modification, Bag-of-Freebies Modification, Airborne Object*

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PREFACE

This research was made as a final project to fulfill the graduation requirement in Computer Engineering Department of ELECTICS - ITS. The dataset used in this research is under CDLA-Permissive 1.0. Figures and tables reproduced in this report was either under creative commons license or reproduced with the original author's permission.

I would like to thank both my advisors Reza Fuad Rachmadi, S.T., M.T., Ph.D and Dr. I Ketut Eddy Purnama, S.T., M.T. who had given me guidance to complete this final project. Also, I would like to thank the red computer in B201 lab, who has worked hard running gradient descent to train models for this project. Last but not least, I would like to thank my friends who made working on this final project less boring.

Surabaya, July 2023

Dion Andreas Solang

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CHAPTER I

INTRODUCTION

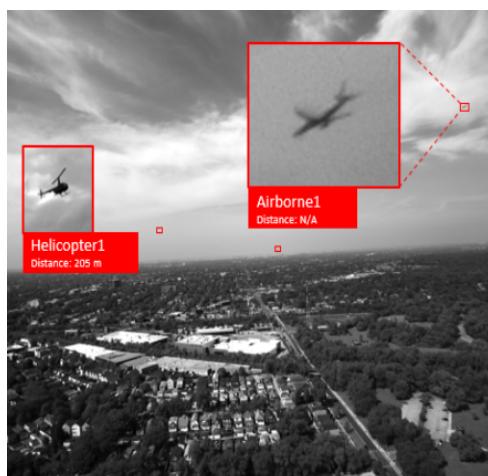
1.1 Background

Autonomous Aerial Vehicle (AAV) have the potential to significantly impact industries, particularly in commercial delivery. One notable example is Amazon Prime Air, which is currently under development. Prime Air aims to deliver goods from Amazon warehouses directly to customers (Amazon, 2022). To accomplish this, AAV require a reliable and efficient autonomy system.

One of the most critical challenges in designing an AAV system is the ability to sense and avoid (SAA) obstacles. While the airspace in which AAVs operate may be relatively sparse, there is still risk of encountering static obstacles or airborne objects such as birds or drones. In commercial applications, such encounters can have consequences not only for the AAV itself but also for the items it carries. Ensuring effective SAA capabilities is essential to mitigate these risks and safeguard both the AAV and the valuable cargo it transports.

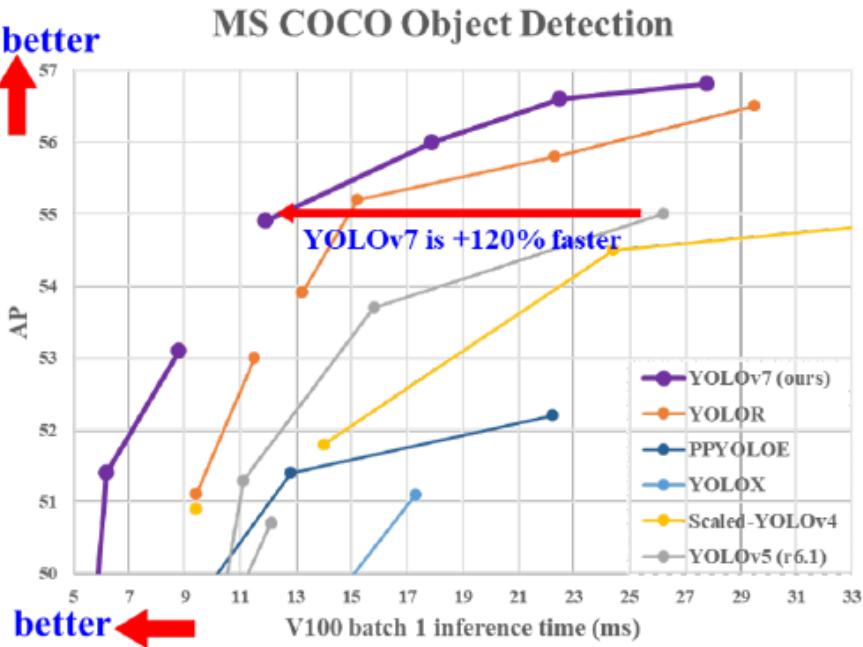
Most SAA system of AAVs includes camera as their primary sensor. Cameras provide visual perception to the AAV, real-time, in the form of images. These images must be processed by a computer vision algorithm to identify and localize the obstacles in it so that the AAV can estimate their position and plan actions it needs to do to avoid them. There are other onboard sensing options such as LiDAR or radar, but cameras are more favored due to their lighter weight, cheaper price, and relatively lower energy consumption compared to active sensors.

Airborne objects present a particularly challenging problem in SAA as they can appear unexpectedly and approach rapidly from long distances due to their inherent need for speed in flight. For this reason, it is important to detect airborne objects while they are still far away. Unfortunately, their far distance cause them to appear very small on images. Figure 1.1 show an example of how airborne objects appear on images. In “Airborne Object Tracking Challenge”



Source: “Airborne Object Tracking Dataset” (2021) under CDLA-Permissive 1.0

Figure 1.1: An example of airborne object dataset



Source: C.-Y. Wang, Bochkovskiy, et al. (2022) with permission (see Appendix C)
 Figure 1.2: YOLOv7 performance on COCO dataset compared to other object detectors.

(2021), the airborne objects can appear in the range of 4 to 1000 px on a 2048×2448 px image, that is, around 0.00008 - 0.01 % of the image area.

For reasons listed above, the computer vision algorithm to be implemented to detect these airborne objects, must be able to detect small objects accurately. And not only that, it also must be able to do it in real-time. The fact that AAVs operating environments are outdoors, brings more trouble for the computer vision. Outdoor environment brings large complexity and additional variance to the image distribution, making it almost impossible to handcraft feature extractor for it. This is where non-handcrafted feature extractors come in handy, particularly the deep learning approaches. Deep learning models have shown incredible abilities in handling complex data. Given enough training data, a deep learning model can craft itself feature kernels that can extract the objects in an image, despite being subjected to complex outdoor environment. For this reason, deep learning models gained prominence in addressing these challenges.

Introducing YOLOv7, a state-of-the-art convolutional neural network based real-time object detector (C.-Y. Wang, Bochkovskiy, et al., 2022). At the time of the proposal for this research was made (November 2022), YOLOv7 outperform both in speed and accuracy of all known real-time object detectors with inference speed in the range of 5-160 FPS as seen on Figure 1.2. It also has the highest accuracy (56.8% AP) among object detectors with inference speed greater than 30 FPS on a V100 GPU. The capabilities of this cutting-edge architecture makes it well-suited for AAV computer vision system. However, all the performance metrics of YOLOv7 mentioned before are obtained by training the model using COCO 2017 dataset. A dataset which consist of general objects that people see in their daily life. COCO dataset is going to have very distinct distribution compared to airborne objects. As such, there would be a need for some modification to YOLOv7 so that it could detect airborne objects well.

The topic of this research is about modifying YOLOv7 with objective of optimizing it to detect small objects, which extends to airborne objects. We experimented with some mod-

ification to YOLOv7’s bag-of-freebies, bag-of-specials, and network architecture. Then we benchmarked the modified models against the “Airborne Object Tracking Dataset” (2021), and picked the model with the highest AP score that can perform inference in real-time.

1.2 Problem Statement

In this research, our primary focus will be on the modifications of YOLOv7 to enhance its ability in detecting airborne objects. Rather than aiming for the ultimate solution for detecting airborne objects, our objective is to explore potential modification to YOLOv7 that can improve its performance in small object detection. Therefore, the problem statement of this research is as follows:

What specific modifications can be implemented on YOLOv7 to improve its abilities in detecting airborne objects?

1.3 Purpose

The purpose of this research is to identify and propose practical improvements to YOLOv7 that can improve its ability in detecting airborne objects. This research seeks to contribute to the improvement of YOLOv7 in the context of airborne object detection, ultimately leading to more reliable and efficient detection capabilities in relevant applications such as SAA systems.

1.4 Problem Scope

In this research, we want to formulate the scope of the problem such that the modifications applied on YOLOv7 would not lose its real-time detection ability and is still reasonably computable/trainable. Otherwise, we can just run a Solomonoff induction on airborne object data and call the result a modification of YOLOv7. Thus, we state the following scopes for the problem.

1. YOLOv7 is used as the basis for modifications.
2. The result of modification must be able to perform inference in real-time with consumer-level GPU.
3. The modified YOLOv7 is subject to computational resource constraint. The modified model must be trainable within a reasonable duration using the computational resource available.

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CHAPTER II

LITERATURE REVIEW

2.1 Theoretical Basis

In this section, the underlying theoretical foundation and conceptual framework for this research will be explained.

2.1.1 Object Detection Task

Object detection is a fundamental task in computer vision. It is a task that have 2 objective, localization and classification. Localization is about determining the spatial properties of an object in an image. E.g. by enclosing objects in bounding boxes, determining which part of the image is an object and which part is not. On the other hand, classification is about determining the class of objects. An object detection algorithm has to determine the label of an object whether they are an animal, human, necromancer, or something else in the set of classes.

To measure how well an object detection algorithm or model perform, computer vision researchers defined metrics to measure how fit a model prediction to an object and to measure how well the model perform across all objects. Example of those metrics are Intersection Over Union (IoU) and Mean Average Precision (mAP).

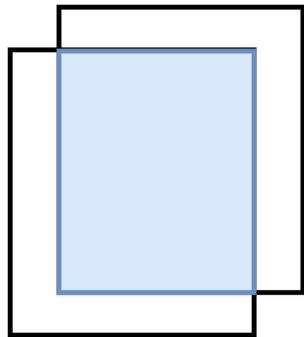
Intersection Over Union

IoU is a widely used metrics to determine how fit a predicted bounding box against the true bounding box. It is done by calculating the area of the intersection between the predicted and dividing it by the area of the union of those 2 boxes. This way, IoU is robust to objects of different sizes and aspect ratio.

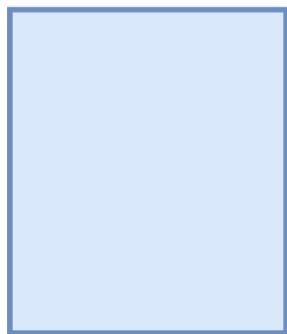
Bounding box of an object can be large, small, wide, or tall. Since IoU consider the intersection of bounding boxes in relation to the union, IoU provides a normalized measure of the fitness of boxes, making it robust to the bounding boxes size. For example, if 2 boxes A and B intersect, there would be three possible cases, A fits B perfectly, A is inside B or vice versa, and some of A in B or vice versa as shown in Figure 2.1. When bounding box A fits B perfectly, the value of IoU would be 1 as the area of intersection is the same as the area of union. For the case where a bounding box is inside another, IoU can lower the score if the enclosed box's size is smaller compared to the enclosing box due to the normalization by the union area. For the case when the boxes partly intersect, the area of intersection and area of union would be suboptimal, leading to a lower IoU score. We can say that the intersection part of the IoU provide a score for the bounding boxes position similarities and the union provide score for size similarities.

To calculate the IoU of two bounding boxes A and B, the area of intersection and union must first be calculated. The following shows the process of calculating IoU.

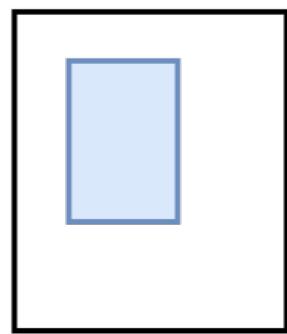
1. Calculate the area of intersection of A and B. Let (x_A, y_A) and (x_B, y_B) be coordinates of the center of the boxes A and B respectively, and let (w_A, h_A) and (w_B, h_B) be widths and heights of boxes A and B, as demonstrated in Figure 2.2.



(a) Bounding Boxes Partly Intersect



(b) Bounding Boxes Fully Intersect



(c) Bounding Box Inside Another Bounding Box

Figure 2.1: Three Cases of Bounding Boxes Intersection

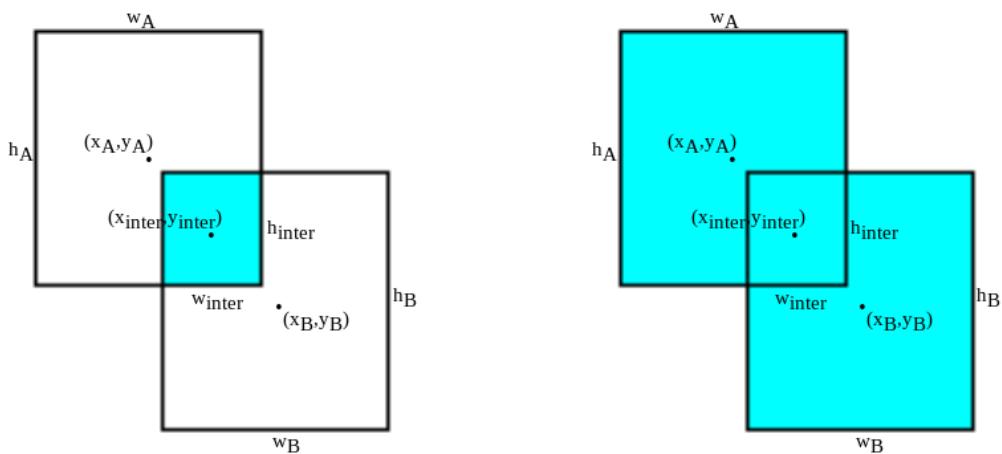


Figure 2.2: Important Points For IoU Calculation

The calculation for the area of intersection can be done like this:

$$\begin{aligned}x_{\text{inter}} &= \max(x_A, x_B) \\y_{\text{inter}} &= \max(y_A, y_B) \\w_{\text{inter}} &= \min(x_A + w_A, x_B + w_B) - x_{\text{inter}} \\h_{\text{inter}} &= \min(y_A + h_A, y_B + h_B) - y_{\text{inter}} \\ \text{Area}_{\text{inter}} &= w_{\text{inter}} \times h_{\text{inter}}\end{aligned}$$

2. Calculate the area of union.

From set theory, we know that $|A \cup B| = |A| + |B| - |A \cap B|$. This equation also applies on calculating the area of union.

$$\begin{aligned}\text{Area}_{\text{union}} &= \text{Area}_A + \text{Area}_B - \text{Area}_{\text{inter}} \\ \text{Area}_{\text{union}} &= w_A \times h_A + w_B \times h_B - \text{Area}_{\text{inter}}\end{aligned}$$

3. Finally, calculate IoU

$$IoU = \frac{\text{Area}_{\text{inter}}}{\text{Area}_{\text{union}}} \tag{2.1}$$

Mean Average Precision

Average Precision (AP) is a popular metrics used to measure the capability of an object detection model for a given dataset. The main advantage of using AP are its ability to capture the precision recall tradeoff and its independence towards confidence threshold. AP has these 2 advantage as an effect of the way it is calculated.

Calculating AP is the same as calculating area under the curve (AUC) of precision and recall curve. Precision is defined as

$$P(\mathbb{S}_c, h, \tau, \epsilon) = \frac{\left| \{(\hat{B}, x) \in \mathbb{S}_c : \exists B \in h(x, \tau)_c, IoU(\hat{B}, B) > \epsilon\} \right|}{\sum_{x \in \mathbb{S}_{x,c}} |B \in h(x, \tau)_c|} \tag{2.2}$$

Where h = hypothesis/model that predict bounding boxes

\mathbb{S}_c = set of bounding boxes of class c in dataset paired with their respective image

$h(x, \tau)_c$ = bounding boxes predicted by h with class c

τ = confidence threshold for h

ϵ = IoU threshold for a positive prediction

B = Bounding box

x = image

and for recall, it is defined as

$$R(\mathbb{S}_c, h, \tau, \epsilon) = \frac{\left| \{(\hat{B}, x) \in \mathbb{S} : \exists B \in h(x, \tau)_c, IoU(\hat{B}, B) > \epsilon\} \right|}{|\mathbb{S}_c|} \quad (2.3)$$

Then we define the precision recall curve as a parametric function

$$PR(\tau) = (R(\mathbb{S}_c, h, \tau, \epsilon), P(\mathbb{S}, h, \tau, \epsilon)) \quad (2.4)$$

Using equation 2.4, PR points in Figure 2.3 can be generated using $0 \leq \tau \leq 1$. Before calculating the AP however, the curve in Figure 2.3 is usually interpolated using Equation 2.5, which relies on Equation 2.6 that transformed PR curve to a functional relation of R to P. The interpolated curve can be seen on 2.4

$$p_{inter}(r) = \max_{\bar{r} > r} p(\bar{r}) \quad (2.5)$$

$$\text{Where } p(\bar{r}) = \max \{p : \forall (r, p) \in \{PR(\tau) : 0 \leq \tau \leq 1\} \wedge r = \bar{r}\} \quad (2.6)$$

The AP, which is the area under the curve then can be calculated using the following integral:

$$AP = \int_0^1 p_{inter}(r) dr \quad (2.7)$$

When calculating AP, the IoU threshold for positive detection is usually predefined. As example, for AP@50, we set the ϵ in Equation 2.2 and 2.3 to 50%. And for AP@75, the ϵ is set to 75%.

The AP calculation so far only works for a single class. To have a multiclass metric, we use mAP which is calculated as the average AP across all classes in the dataset.

$$mAP@X = \frac{1}{|\text{classes}|} \sum_{c \in \text{classes}} AP_c @ X \quad (2.8)$$

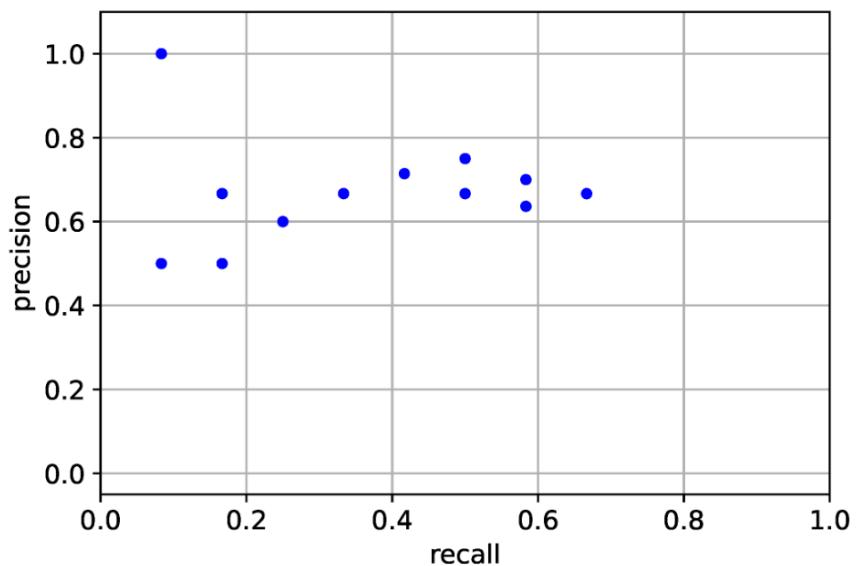
2.1.2 Neural Network

Neural Network are computational models that drew inspiration from how neural network in brain works. It imitates a simplification model of human brain which consist of large number of simple computational block (neuron) that are connected to each other, but able to carry out complex computation (Shalev-Shwartz & Ben-David, 2014).

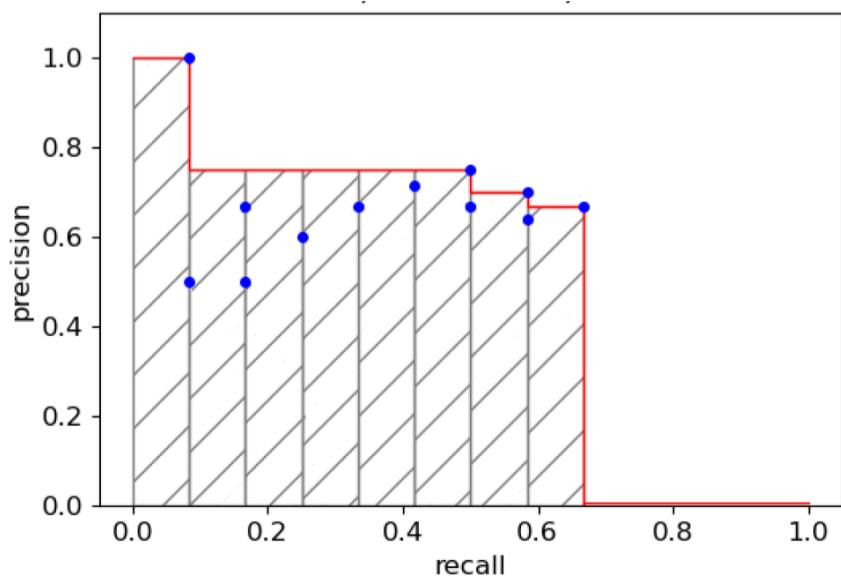
Mathematically Modeling Neural Network

A neural network can be described as directed graph where each node of the graph is a neuron and the edges are the link between the neurons. Each neuron will take the weighted sum of the output of other neurons that are connected to it via incoming edge, and will output a value that would be an input to another neuron. We can describe a neural network with a graph $G = (V, E)$ and a weight function $w : E \rightarrow \mathbb{R}$, where each node is modeled as activation function $\sigma : \mathbb{R} \rightarrow \mathbb{R}$.

To simplify explanation here like how Shalev-Shwartz and Ben-David (2014) did, we assume the neural network form a feed-forward neural network (DAG structure) and is organized



Source: Padilla et al. (2021) under CC BY 4.0
Figure 2.3: PR Points Generated by Varying τ



Source: Padilla et al. (2021) under CC BY 4.0
Figure 2.4: PR Curve Interpolated

in layers. We can say that each node in V can be decomposed as a union non-empty disjoint subsets of nodes, $V = \coprod_{t=0}^T V_t$, such that every edge in E connect some node in V_{t-1} to V_t for $t \in [T]$.

We call V_0 , the first layer of the neural network as the input layer. It has $n_0 + 1$ nodes where n_0 is the dimensionality of input space. For every i in $[n_0]$, the output of neuron i is just x_i , the values of input vector \vec{x} . The last neuron in V_0 is a constant neuron that always outputs 1. We denote $v_{t,i}$ to be the i -th neuron of the t -th layer and $o_{t,i}(\vec{x})$ as the output of that neuron when the neural network is fed with input vector \vec{x} .

Now we can perform the neural network calculation in layer-by-layer manner. Let $a_{t+1,j}(\vec{x})$ be the input to $v_{t+1,j}$ when the network is fed with \vec{x} . We can calculate a with the following:

$$a_{t+1,j}(\vec{x}) = \sum_{r:(v_{t,r}, v_{t+1,j}) \in E} w((v_{t,r}, v_{t+1,j})) o_{t,r}(\vec{x}), \quad (2.9)$$

and o can be calculated with:

$$o_{t+1,j}(\vec{x}) = \sigma(a_{t+1,j}(\vec{x})) \quad (2.10)$$

Equation 2.9 shows how the input of the neuron in the next layer is the weighted sum of the neurons in the previous layer that is connected to that neuron. The weighted sum are regulated according to w , and Equation 2.10 shows how the output of a neuron $v_{t+1,j}$ is only the application of activation function σ on its input.

The layers beside the input layer V_0 and output layer V_T are often called hidden layers. T , the number of layers in the neural network, sometimes referred to as the depth of the network, hence the name deep learning. $|V|$ is called the size of the network and $\max_t |V_t|$ is called the width of the network.

An illustration of the layers in a neural network can be seen on Figure 2.5. The illustrated neural network has a depth of 2, size of 10, and width of 4.

Neural Network as Hypothesis Class

Previously, we have specified a neural network architecture using V , E , and σ . This architecture is a hypothesis class or model class that consist of functions $h_{V,E,\sigma,w} : \mathbb{R}^{|V_0|-1} \rightarrow \mathbb{R}^{|V_T|}$. With V , E , and σ fixed, we can define the hypothesis class of the neural network architecture by:

$$\mathcal{H}_{V,E,\sigma} = \{h_{V,E,\sigma,w} : w \text{ is a mapping of } E \rightarrow \mathbb{R}\} \quad (2.11)$$

Equation 2.11 means that to find a model in the hypothesis class \mathcal{H} , we can do so by specifying the weights of the edges w .

Neural Network Learning

The learning of a neural network is the searching for the best hypothesis/model from hypothesis class \mathcal{H} . To find a model in $\mathcal{H}_{V,E,\sigma}$ with a low risk over the data by tuning w , we can apply some heuristic search approach by stochastic gradient descent (SGD).

We can think of the weight function w as a vector \vec{w} in $\mathbb{R}^{|E|}$. If $n = |V_0| - 1$ the number of input neurons and $k = |V_T|$ the number of output neurons, we can call a hypothesis defined by \vec{w} in the hypothesis class to be a function $h_{\vec{w}} : \mathbb{R}^n \rightarrow \mathbb{R}^k$. Let $\Delta(h_{\vec{w}}(\vec{x}), \vec{y})$ be the loss of predicting $h_{\vec{w}}(\vec{x})$ when the target label is \vec{y} . The risk of the network over data distribution \mathcal{D} can be defined

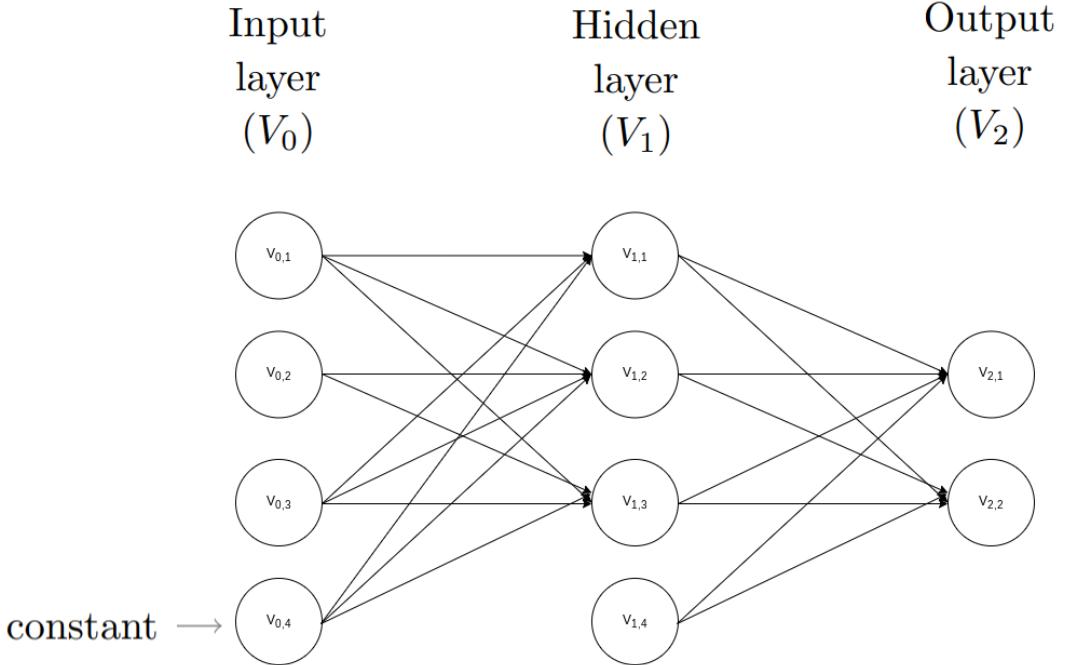


Figure 2.5: Illustration of neural network with $T = 2$

as in Equation 2.12:

$$L_{\mathcal{D}}(\vec{w}) = \mathbb{E}_{(\vec{x}, \vec{y}) \sim \mathcal{D}} [\Delta(h_{\vec{w}}(\vec{x}), \vec{y})] \quad (2.12)$$

Now, we can use SGD to do empirical risk minimization (ERM) according to risk in Equation 2.12. The ERM can be done by setting the \vec{w} to be a random vector, and perform SGD with the data. The gradients of each element in \vec{w} however does not have a closed form. Instead, it is calculated using backpropagation. Sometimes it is also useful to add regularization term to the risk equation, that is, we try to minimize $L_{\mathcal{D}} + \frac{\lambda}{2} \|\vec{w}\|^2$ for better result.

2.1.3 YOLO Family Architecture

YOLO is an abbreviation of "You Only Look Once" which describes what kind of neural network YOLO is, a single stage object detector. It means that this architecture predicts regions and classes both at once. In contrast, two-stage detector predicts objects' regions first and then predicts their classes. Detecting objects in a single-stage manner is what gave YOLO architecture the ability to infer in real-time. This is possible due to how YOLO architecture was designed. YOLO architecture consist of 3 main part, the head, the neck, and the backbone.

Backbone

The backbone is the network that extract features from the inputted image. Typically, the backbone is composed of deep neural network layers that progressively down sample the spatial dimensions of the input while increasing the number of learned features or meaningful abstraction of the data.

The implementation of backbone in YOLO usually varies from one version to another. As example, Redmon and Farhadi (2016)'s YOLOv2 implemented Darknet-19 network as backbone, Redmon and Farhadi (2018)'s YOLOv3 implemented Darknet-53, Bochkovskiy et al. (2020)'s YOLOv4 with their CSP-Darknet-53, and Zhang et al. (2021) with their non-CNN

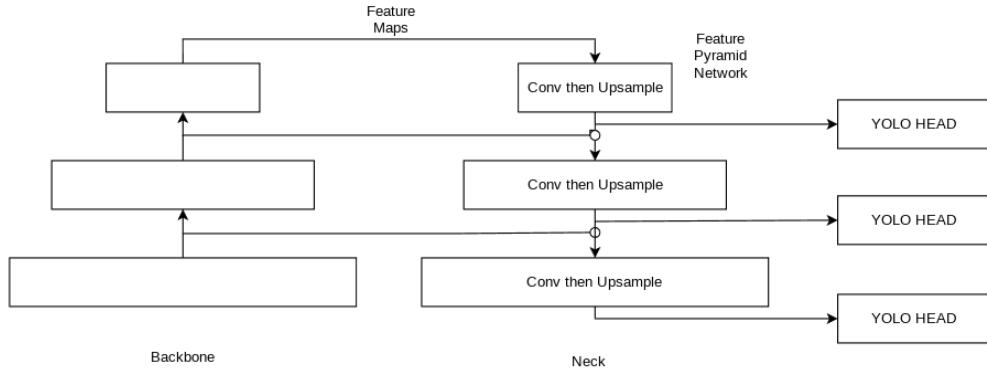


Figure 2.6: Feature Pyramid Network in YOLOv3

(Transformer) backbone. Each of these network has their own has their own advantages and disadvantage when it comes to accuracy, memory requirement, or latency.

The Neck

The neck is the intermediate network between backbone and head and its main function of the neck is to enhance features extracted by the backbone. The specific implementation of neck for each YOLO architecture is different one to the other, however. One common approach is to combine feature maps from different prediction scales of the YOLO network.

In YOLOv3, Redmon and Farhadi (2018) introduced prediction in multiple scale. To utilize information across scales, YOLOv3 fuses features from multiple parts of the backbone before feeding them to the head as seen on Figure 2.6 by using Feature Pyramid Network (FPN) as its neck.

A further improvement was made by Bochkovskiy et al. (2020) with their YOLOv4 by introducing Path Aggregation Network (PANet) for the neck. With PANet, feature are fused back to higher scale by adding another FPN-like layer after the original FPN but with reverse direction. This way, the features fused not only top to bottom but also bottom to top, making top feature have information learned by bottom feature and vice versa. This result in a better integration of multiscale information and increased the object detection accuracy.

Overall, the neck's role in YOLO architectures is to facilitate feature enhancement and fusion across different scales to improve detection performance.

The Head and The Anchors

The head is where the object detection happens. Extracted and enhanced features of the image is fed to the head in multiple different scales. For each scale, the head will predict a box for each $N_k \times N_k$ lattice point on feature map's grid. In total, each layer will output a tensor with size $N_k \times N_k \times [A_k \times (4 + 1 + C)]$ where N_k is the size of feature map grid at the k -th scale, A_k is the number of anchors for that scale, 4 is for the four offsets $[t_x, t_y, t_w, t_h]$ (see Figure 2.7), 1 is for the objectness score for the grid, and C is for the number of classes it has to predict.

Most of YOLO family architecture head utilizes anchor boxes to assist bounding box prediction. This technique is used in Redmon and Farhadi (2016), Redmon and Farhadi (2018), Bochkovskiy et al. (2020), C.-Y. Wang et al. (2020), Jocher et al. (2022), C.-Y. Wang et al. (2021), and C.-Y. Wang, Bochkovskiy, et al. (2022). Instead of directly predicting the size and

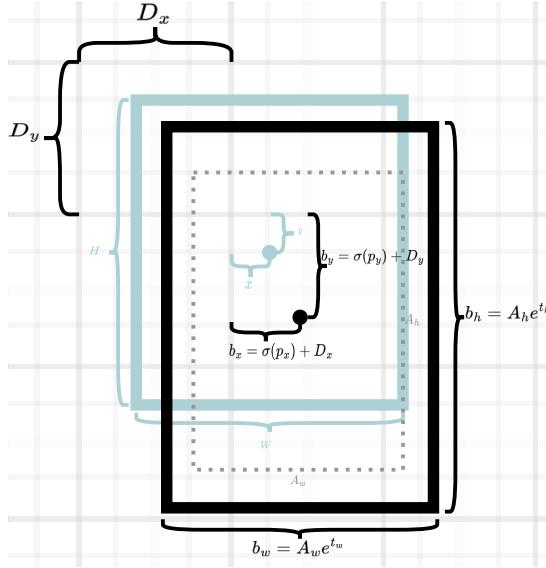


Figure 2.7: Prediction for Anchor Box and Its Offsets from Lattice of The Feature Grid

position of the bounding box, YOLO head predicts the offsets for each anchor boxes assigned to the head, then it utilizes the objectness score to pick which result of these anchor boxes to be used. Using anchor boxes allows the neural network to converge more quickly because it provides a prior knowledge of the dataset before training.

Loss Function

The goal of a YOLO architecture is to (1) predict if an object exist or not, (2) predict the bounding box of such object, and (3) predict the class of the object. These 3 loss functions that correspond to those objectives are called objectness loss, box loss, and class loss respectively. To update the weights on training, the total loss is calculated as the weighted sum of those 3 losses. In original YOLO, the loss functions were defined like the following. For localization loss, it is described by equation 2.13.

$$L_{box} = \sum_{i=0}^{S^2} \sum_{j=0}^B \mathbb{1}_{ij}^{obj} \left[(x_i - \hat{x}_i)^2 + (y_i - \hat{y}_i)^2 + (\sqrt{w_i} - \sqrt{\hat{w}_i})^2 + (\sqrt{h_i} - \sqrt{\hat{h}_i})^2 \right] \quad (2.13)$$

Where S^2 = the total number of grid cells in the output,

B = the total number of anchor box per grid cells,

$$\mathbb{1}_{ij}^{obj} = \begin{cases} 1, & \text{if object present in grid} \\ 0, & \text{otherwise,} \end{cases}$$

(x_i, y_i) = the predicted coordinates of the center of object i

(\hat{x}_i, \hat{y}_i) = the ground truth coordinates of the center of object

(w_i, h_i) = the predicted width and height of object i

(\hat{w}_i, \hat{h}_i) = the ground truth width and height of object

For objectness loss, described by equation 2.14

$$L_{obj} = \sum_{i=0}^{S^2} \sum_{j=0}^B \mathbb{1}_{ij}^{obj} (C_i - \hat{C}_i)^2 + \alpha \mathbb{1}_{ij}^{noobj} (C_i - \hat{C}_i)^2 \quad (2.14)$$

Where $\mathbb{1}_i^{noobj} = \begin{cases} 1, & \text{if object assigned to anchor j} \\ 0, & \text{otherwise} \end{cases}$

(C_i, \hat{C}_i) = predicted and ground truth confidence score for objectness of anchor

α = weight to punish false positives

And for class loss, described by 2.15

$$L_{class} = \sum_{i=0}^{S^2} \mathbb{1}_{ij} \sum_{c \in classes} (p_i(c) - \hat{p}_i(c))^2 \quad (2.15)$$

Where $(p_i(c), \hat{p}_i(c))$ are the predicted and ground truth class probabilities for class c for object i .

The three losses combined to the final loss function in equation 2.16

$$L = \lambda_{box} L_{box} + \lambda_{obj} L_{obj} + \lambda_{class} L_{class} \quad (2.16)$$

Where λ_{box} = the weight for localization,

λ_{obj} = weight for objectness

λ_{class} = weight for class

These 3 λ -s can be tuned to optimize the performance of a YOLO network.

2.1.4 YOLOv7

As said in section 1.1, YOLOv7 is the state-of-the-art real-time object detector. It was made by the authors of YOLOv4, and by the time it was published (July 2022), it surpassed all known real-time object detectors both in speed and accuracy. To achieve this, YOLOv7 implemented some new changes and addition to the neural network.

Backbone

YOLOv7 implemented the Efficient Layer Aggregation Network (ELAN) and Extended-ELAN (E-ELAN) as the backbone of its network. ELAN is a convolutional neural network that was designed to extract features efficiently by controlling the shortest longest gradient path in the network (C.-Y. Wang, Liao, & Yeh, 2022). This choice of backbone allows YOLOv7 to perform prediction more accurately despite having fewer number of parameters.

Figure 2.8b shows how ELAN block in Figure 2.8a implemented in YOLOv7. First, the $640 \times 640 \times 3$ input x propagate through 3 convolution layers, down-sampling the dimension to 160×160 and increased the channels to 128. Then it encounter the first ELAN block. ELAN block did not change the dimension, but it doubled the number of channels, making the

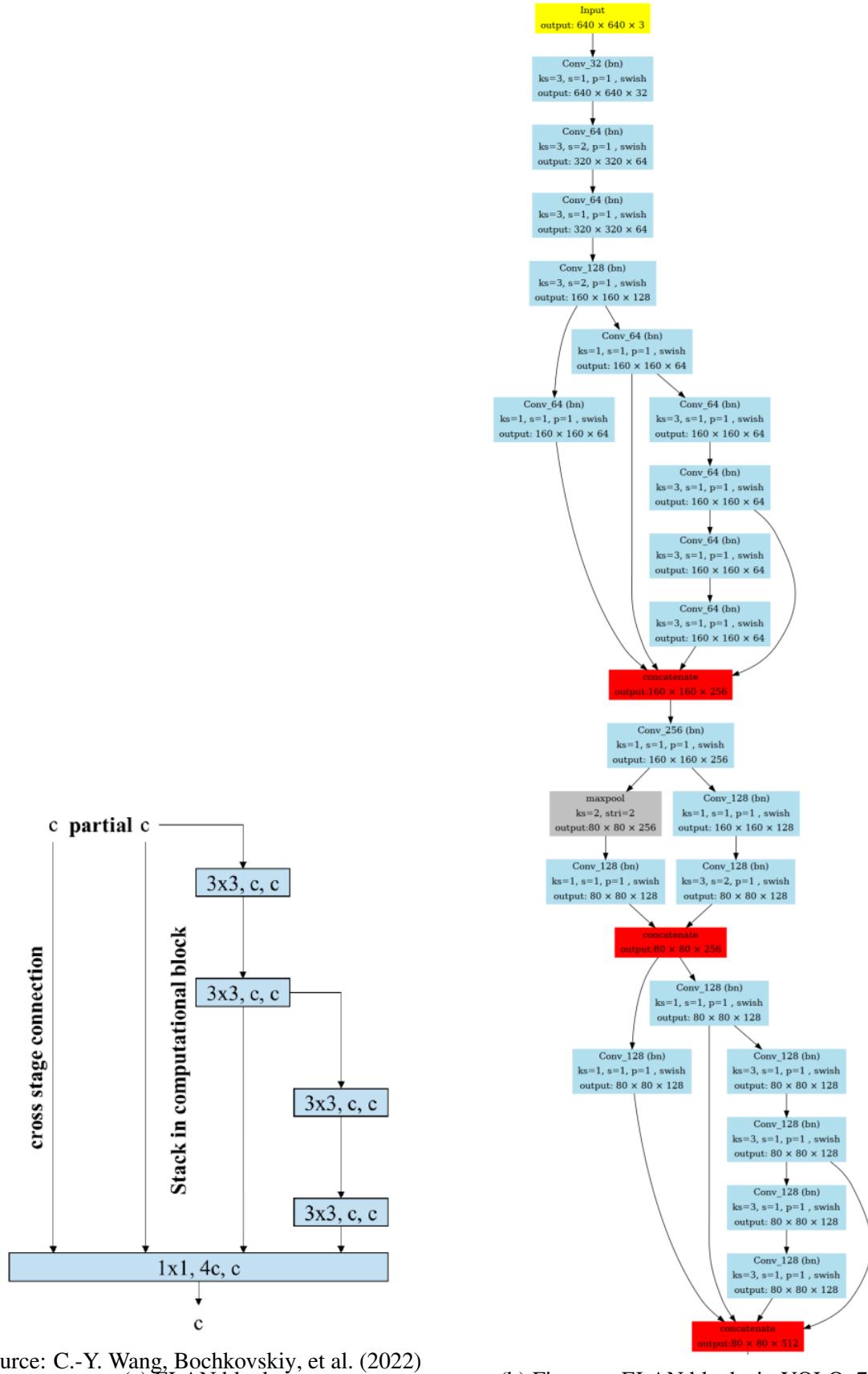


Figure 2.8: ELAN in YOLOv7

dimension of x to be $160 \times 160 \times 256$. Before propagating x to the next ELAN layer however, x is down-sampled to $80 \times 80 \times 256$ using max-pooling and convolution layers. Prior to each ELAN layers in the backbone, the feature will be down-sampled in its width and height dimension by half.

Label Assignment Strategy and Auxiliary Head

SimOTA, first introduced in YOLOX, is an algorithm to approximate Optimal Transport Assignment (OTA) in a faster way. Ge et al. (2021) introduced SimOTA in YOLOX because OTA was deemed too slow to compute as it was increasing the training time by 25%. YOLOv7 also implemented SimOTA for its dynamic label assigner.

YOLOv7 deep supervised its training process by attaching auxiliary heads to its neural network as seen on Figure 2.9a. These auxiliary heads are only used on training, on inference, they are removed from the neural network to improve latency, only the lead head is kept. There is a problem however with assigning labels to the auxiliary and lead heads. Most object detection networks that utilizes auxiliary heads have 2 independent label assigners, one for auxiliary heads and one for lead heads. YOLOv7 done things differently.

YOLOv7 proposed 2 way of assigning labels to auxiliary and lead heads. Lead head guided label assignment (Figure 2.9b) and coarse-to-fine lead head guided assignment (Figure 2.9c). For lead head guided label assignment, the assigner gives a copy of lead heads' label assignment to the auxiliary heads. For coarse-to-fine lead head guided assignment, the assigner works like lead head guided assigner but gives coarse label assignment to auxiliary head. Coarse label assignment is done by relaxing the positive sample constraints of the assigner.

Due to the relaxed constraints, coarse label assignment to auxiliary heads assigns more positive labels the auxiliary heads' grids. This way, the network will learn more to recall. On inference, this recall ability would be filtered by the lead head to produce accurate prediction. C.-Y. Wang, Bochkovskiy, et al. (2022) find that coarse-to-fine label assignment produces the greatest AP scores.

Reparameterization

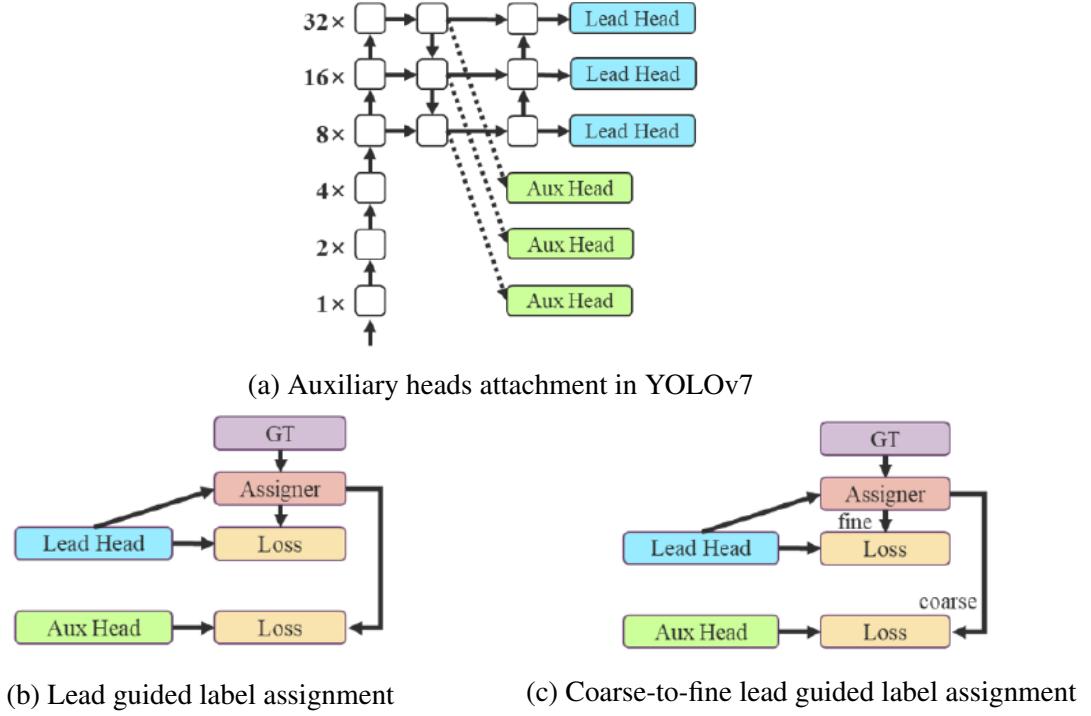
YOLOv7 utilized RepConv and YOLOR implicit layers in its network. In addition to that, YOLOv7 also uses Convolution-BatchNorm layer. These layers can be reparameterized after training to simplify the neural network, thereby reducing latency and memory usage but not hurting inference performance.

The reparameterization of these layers can be done after training by computing some mathematical simplification of some layer combination. These combinations of layers are YOLOR⁺–Convolution–YOLOR⁺, YOLOR^{*}–Convolution–YOLOR^{*}, and Convolution-BatchNorm.

For combination of layers YOLOR⁺–Convolution–YOLOR⁺ layers, it can be reparameterized like the following.

$$\begin{aligned} x_{n+1} &= W(x_n + g_1(z_1)) + b + g_2(z_2) \\ &= W(x_n) + (W(g_1(z_1)) + b + g_2(z_2)) \\ &= W(x_n) + b' \end{aligned}$$

Observe that the reparameterization combined 3 layers into a single convolution layer with bias.



Source: C.-Y. Wang, Bochkovskiy, et al. (2022) with permission (see Appendix C)
 Figure 2.9: YOLOv7 Label Assignment Strategy with Auxiliary Heads

Then, For combination of YOLOR*-Convolution–YOLOR* layers:

$$\begin{aligned} x_{n+1} &= (W(g_1(z_1)x_n) + b)g_2(z_2) \\ &= g_2(z_2)g_1(z_1)W(x_n) + bg_2(z_2) \\ &= W'(x_n) + b' \end{aligned}$$

And finally for Convolution-BatchNorm:

$$\begin{aligned} x_{n+1} &= ((W(x_n) + b) - m)/s \\ &= (W(x_n) + (b - m))/s \\ &= (W/s)(x_n) + (b - m)/s \\ &= W'(x_n) + b' \end{aligned}$$

In summary, YOLOR⁺–Conv–YOLOR⁺ will be replaced with the original convolutional layer W but with bias $W(g_1(z_1)) + b + g_2(z_2)$. YOLOR^{*}–Conv–YOLOR^{*} layers will be replaced with a convolutional $g_2(z_2)g_1(z_1)W$ and bias $bg_2(z_2)$. And Conv–BatchNorm will be replaced with a convolutional W/s and bias $(b - m)/s$.

2.1.5 Anchor Recalculation

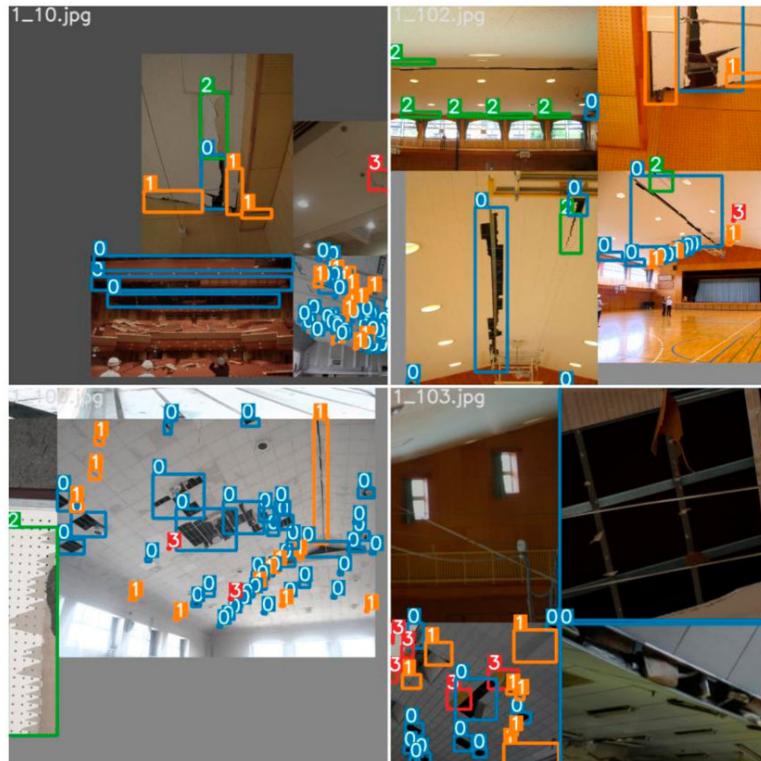
Anchor recalculation is a common method of introducing prior distribution of the dataset to an anchor-based object detection networks. Thus, recalculating anchor can help the neural network learn faster. Most of the time, anchors provided by pretrained YOLO weights are optimized for the common metric dataset such as COCO2017 or VOC2012. Therefore, recalculating anchors in a specific dataset can improve the neural network ability.

There are multiple ways of recalculating anchors. Some of them can be performed before training or during training. Most of pre-training anchor recalculation method involves with clustering the anchors to the dataset. This is done by using clustering algorithm such as K-means, Gaussian Mixture, and many others. Recalculating anchor on training is a little more complex to do as it will involve some loss function or architectural change on the object detection neural network. Zhong et al. (2018) for example add additional layer on detection part of object detectors that is connected to anchor modifiers such that the anchors will also be updated during training. C.-Y. Wang et al. (2021) mentioned that the implicit multiplication layer of their network can be purposed for anchor refinement.

2.1.6 Mosaic Augmentation

Mosaic augmentation was introduced in Ultralytics' implementation of YOLOv3 (Jocher, 2020). This method involves randomly selecting four images from the dataset and tiling them together into a single augmented image, as shown in Figure 2.10. The resulting augmented image has a mosaic-like appearance, thus named "mosaic" augmentation.

Several works (C.-Y. Wang et al., 2019; Bochkovskiy et al., 2020; Jocher et al., 2022) have reported improvements in accuracy when utilizing mosaic augmentation in object detection tasks. By combining multiple images into one, mosaic augmentation provides the model with more diverse training samples, leading to enhanced performance in localizing and classifying objects.



Source: P. Wang et al. (2022) under CC BY 4.0
Figure 2.10: Four example of mosaic augmentation

2.2 Related Works

In this section, we explore several previous works that has similar objective to this research, that is improving YOLO models to detect small objects.

2.2.1 Barunastra ITS' YOLOv4-tiny with added head

Aditya et al. (2022) used YOLOv4-tiny as their Autonomous Surface Vehicle (ASV) object detector due to the computational device constraint. To detect objects that were at least 30 meters away from the ASV, they applied a modification of YOLOv4-tiny, which was YOLOv4-tiny but with additional head layer. The original YOLOv4-tiny only had 2 head layers, thus was only predicting in 2 scales. An addition of head layer allows it to predict in 3 scales. Using this modification, the network was able to detect small object better (as seen on Figure 2.11) and raised the overall mAP score by 4% without significantly reducing latency.

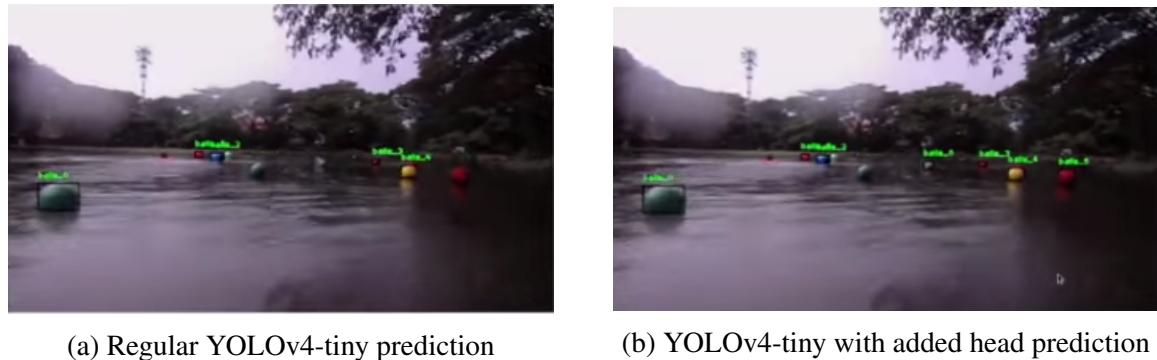
2.2.2 exYOLO

exYOLO is a modification of YOLOv3 to detect small objects (Xiao, 2021). Xiao (2021) thought that the features of small objects in an image would disappear after series stage of down-sampling in the neural network. To solve this, exYOLO added a feature enhancement before feature-fusion in the neck to one of the feature scale as seen in Figure 2.12. This change made exYOLO produce a higher mAP score on VOC2007 compared to its baseline YOLOv3.

2.2.3 YOLO-Z

YOLO-Z is a derivative architecture of YOLOv5r5.0. This variant of YOLO modified the backbone, neck, and number of anchors of the original YOLOv5 to enhance its capability of detecting small objects (Benjumea et al., 2021). These changes are backbone change from YOLOv5r5.0 to a down-scaled DenseNet, neck change from FPN to biFPN on some YOLO-Z scales, and increasing the number of anchors used at each scale. These changes successfully improve the small object detection capability as seen on figure 2.13.

YOLO-Z was aimed to be used in autonomous racing car. In this high speed environment, early detection of obstacle is crucial to plan for action. For that reason, the autonomous racing car must detect the cone-shaped obstacles that are far away from it. Since objects that are far away appear small on image captured by camera, YOLO-Z was designed with purpose of small object detection.

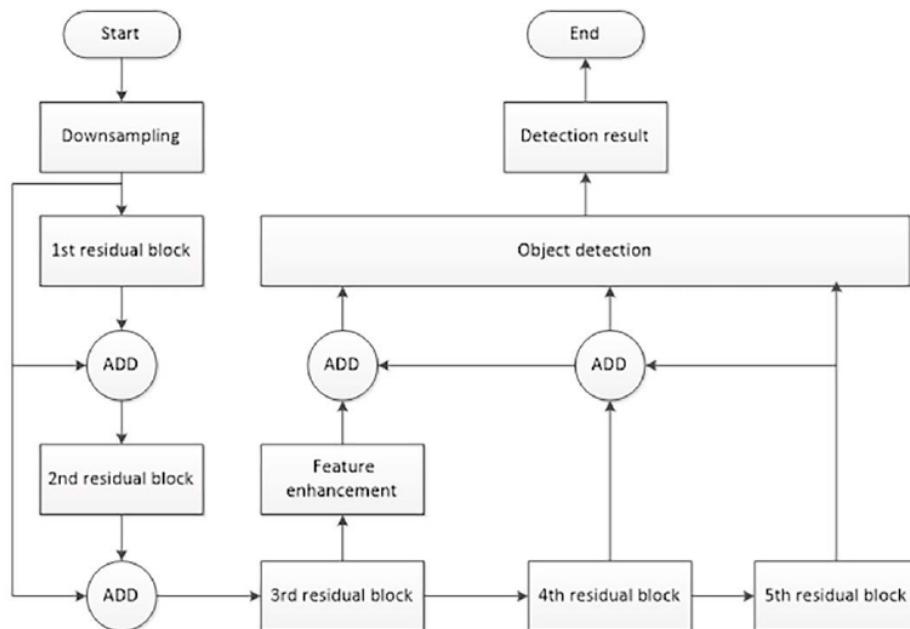


(a) Regular YOLOv4-tiny prediction

(b) YOLOv4-tiny with added head prediction

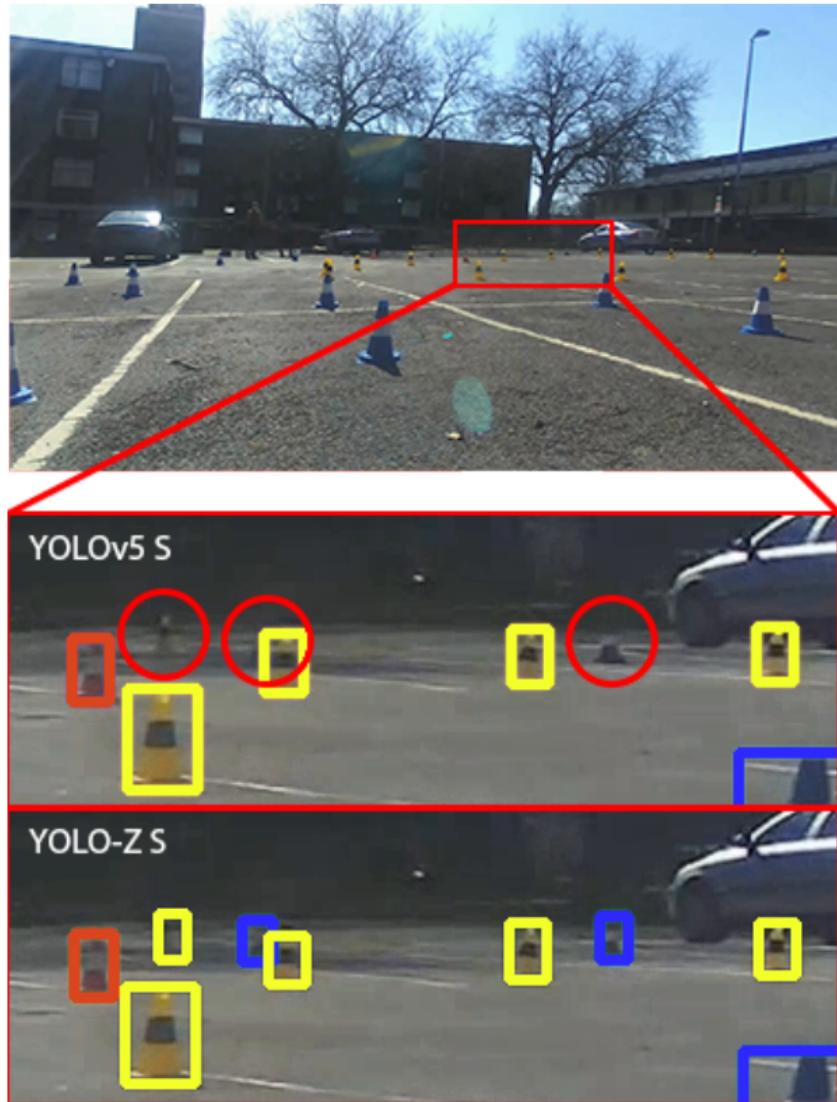
Source: Aditya et al. (2022)

Figure 2.11: Comparison of regular YOLOv4-tiny and YOLOv4-tiny with added head



Source: Xiao (2021) under CC BY-NC-ND 4.0 (see Appendix C)

Figure 2.12: Architecture of exYOLO



Source: Benjumea et al. (2021) with permission (see Appendix C)

Figure 2.13: Small objects in the image. Comparison of YOLOZ-S and YOLOv5-S. YOLOv5-S was not able to detect the circled objects.

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CHAPTER III

METHODS

3.1 Model Searching Method

To find the best model for detecting small objects, trial and error will be performed by introducing modifications to YOLOv7. These modifications can include adding or changing the architecture, bag-of-specials, or bag-of-freebies. These modifications will be tested both independently and in combination with others to evaluate their impact on the model's performance.

The best model will be selected based on *mAP@50* metric. This metric was chosen instead of *mAP@[50 : 95]* because we don't expect for the model to be able to predict a tightly fit bounding boxes for small object and consider a loose 50% coverage IoU is sufficient.

The model searching method consist of six steps that need to be executed. These steps are dataset preparation, develop training system, create modification model configuration, training the model, analysis, and model selection. Figure 3.1 shows the order these steps will be executed.

To conduct this research, we first have to prepare the dataset. First, the dataset will be downloaded from “Airborne Object Tracking Dataset” (2021). Then, the labels of the dataset will be converted to darknet or COCO format. And finally, the dataset will be sampled into training set, validation set, and test set.

The next thing to do is to develop a training system. The purpose of this system is to make the training process easily conducted and monitored. This system will include features such as train fail notification, train queuing, and overheating alert.

Moving on to the next, we have model configuration creation. Here we will create a model configuration file based on the modification that we want to try. The modification configurations will be made according to the modification candidates listed in section 3.2.

The next step is to train the model. The model configurations that was made in previous step will be built and trained from scratch (no pre-trained weights). In this step, the weights of the neural network, training history, and performance metrics will be generated for analysis.

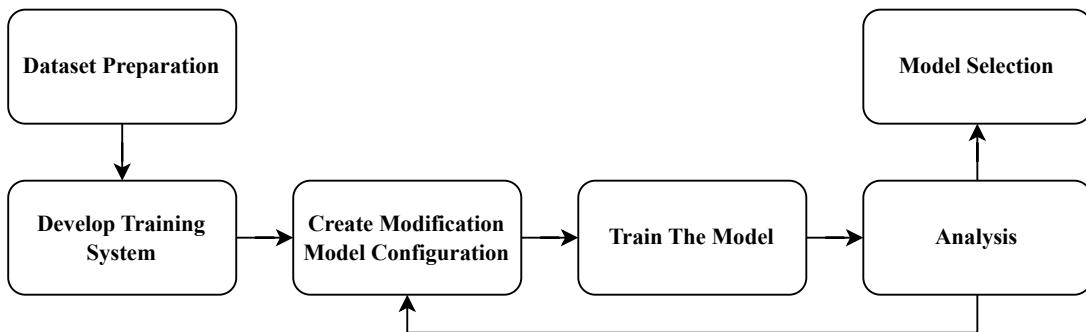
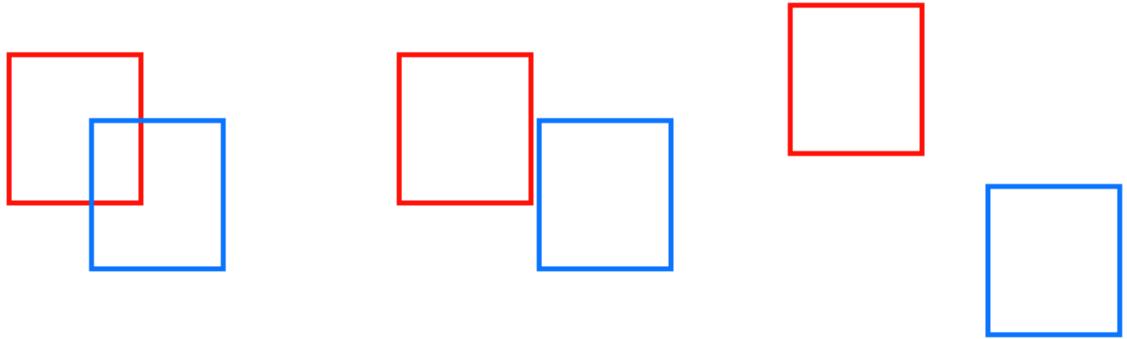


Figure 3.1: Search Steps



(a) $IoU > 0$ when 2 boxes intersect

(b) $IoU = 0$ when 2 boxes does not intersect

(c) $IoU = 0$ when 2 boxes does not intersect and far away

Figure 3.2: Cause of IoU vanishing gradient

In the analysis step, we will analyze the performance of the modified YOLOv7. This step is done to validate the result and to find other candidate of modification that might work. If such modification candidate was found, we will go back to create the model configuration, and then train the modification. This iterative process allows for continuous refinement and enhancement of the modifications capabilities for detecting small objects.

Finally, in the last step we will select the best model. We will select the model with the best performance among the modified YOLOv7 models. The model selection will be done based on *mAP@50* metric, with constraint in inference latency. The model that qualify for selection must be able to perform inference with speed of atleast 10 FPS in a consumer GPU Nvidia RTX 2080Ti.

3.2 Modification Candidates

In this section, the modification candidates that would be tried is explained.

3.2.1 Mosaic Augmentation

As discussed in section 2.1.6, mosaic augmentation was able to increase the detection accuracy of small objects on many object detection neural networks. For this reason, we will experiment by training YOLOv7 with and without mosaic augmentation.

3.2.2 Pre-training Anchor Recalculation

In the implementation code of YOLOv7, the anchors provided was calculated based on COCO2017 dataset. We assume that the dataset distribution of airborne objects to be greatly different from COCO2017. As such, the anchors must be recalculated for better learning. This recalculation will be conducted using k-means algorithm. One problem however is that k-means might fail to cluster the dataset into the amount of anchors that we needed. To tackle this, we might have to cluster it in logarithmic coordinates.

3.2.3 Replacing Localization Loss to Extended IoU

Extended-IoU (EIoU) is a modification of IoU that are used in neural networks to tackle the problem of vanishing gradient (Peng & Yu, 2021). IoU are known to cause vanishing gradient problem due to its behavior when two bounding boxes are not intersecting. When 2 boxes A and

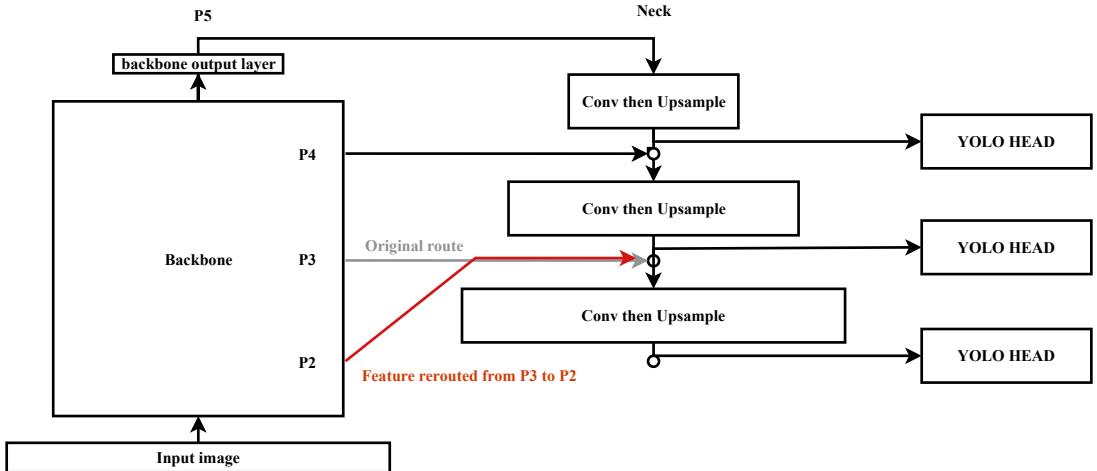


Figure 3.3: Rerouting Neck Connection to Earlier Stage

B are not intersecting, the area of intersection ($A \cap B$) would always be 0. This value doesn't give any information whether the boxes are far apart (Figure 3.2c) or near but not intersecting (Figure 3.2b). To solve this, loss involving IoU are usually paired with some regularization terms. For example Rezatofighi et al. (2019) and Zheng et al. (2019) proposed regularized $IoUs$ named $GIoU$, $DIoU$, and $CIoU$.

YOLOv7 itself is using $CIoU$ for its localization loss. $CIoU$ is just regular IoU that is paired with distance and box aspect ratio regularization terms. The problem of these kinds of regularized IoU is that when the boxes intersect, it does not behave like IoU anymore. $GIoU$, $DIoU$ and $CIoU$ have residue of their regularization when the boxes intersect. Unfortunately, most metrics used to evaluate object detection algorithms depend on IoU (e.g. mAP). For this reason Peng and Yu (2021) designed EIoU. The main appeal of EIoU is that it behaves exactly like IoU when the boxes intersect and gives non-positive value when the boxes do not intersect. By behaving exactly like IoU , it is hoped that the model would perform better on the IoU -based metrics.

3.2.4 Utilizing Earlier Feature Map Stage

In a deep neural network, the extracted feature/abstraction of the data become more prominent as the input data passes through deeper layers. However, so are the loss of information. For small object detection, every information in an image is crucial. There is a possibility that the features of small objects are lost as the data propagates through the network.

If we view it in a data path network design perspective, the greater the length of the path from input to output, the more information will be lost. Therefore, we propose to reroute the original connection from backbone to the neck to an earlier stage of inference. For example, YOLOv7 takes feature maps from P3, P4, and P5 scales of the backbone, we can reroute the connection from P3 to P2 as shown in Figure 3.3. The data path from input image to head routed to P2 is shorter than with P3.

3.2.5 Additional YOLO Head

An additional YOLO head means an extra stage of detection. With more stage of detection, the large variance of the objects in the dataset can be learned. This is especially good for

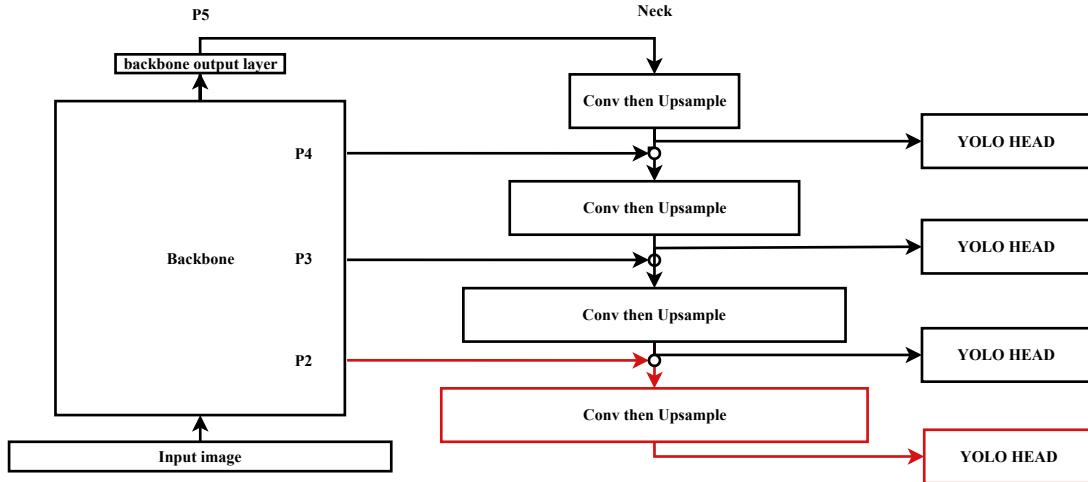


Figure 3.4: Adding an Extra Head Layer

“Airborne Object Tracking Dataset” (2021) where the area of the bounding boxes in the dataset can be orders of magnitude apart as discussed in section 3.5.

3.2.6 Replace YOLO Head to Decoupled Anchor-free Head

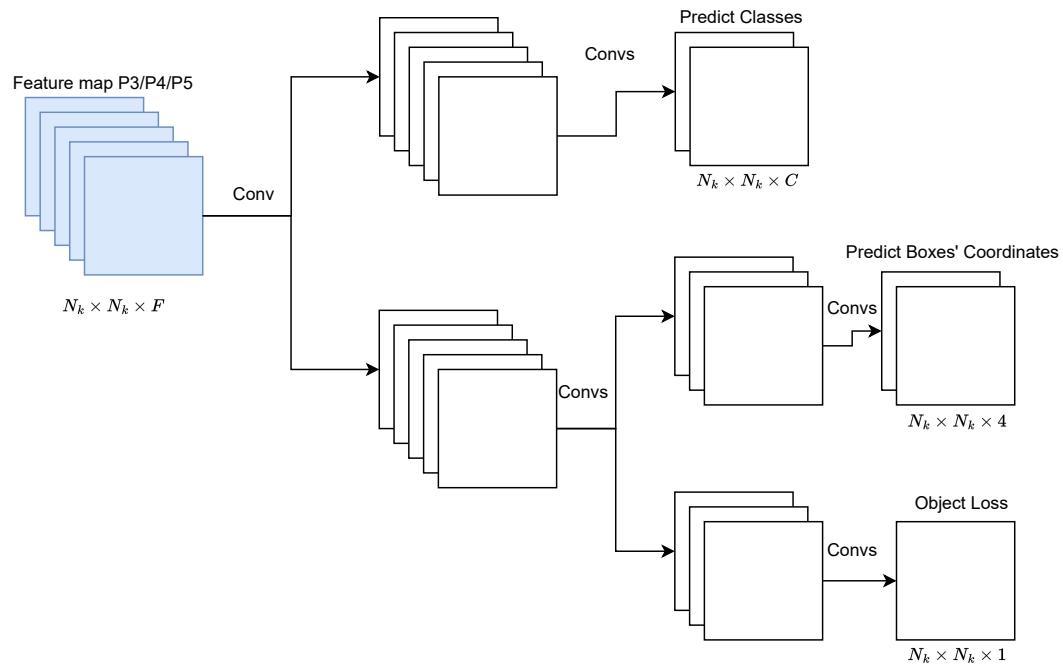
YOLOv6 and YOLOX used a different kind of head layer compared to usual YOLO (Ge et al., 2021; Li et al., 2022). In mainstream YOLO, prediction for bounding box and classes are both calculated on the same layer. With decoupled anchor-free head, the layers are separated for class prediction and bounding box prediction, and bounding box prediction are done using 4 value without anchor as seen on Figure 3.5. Using decoupled anchor-free head gives us 2 advantages. 1) Reducing the amount of design parameters as we don't have to introduce anchor boxes to the model. 2) Reducing the complexity of interpreting prediction result. Advantage (1) is especially enticing. There is a possibility of us introducing bad priors to the neural network by poorly clustering anchor boxes. By having a model that less dependent on prior, we can reduce such possibility.

A thing to consider when applying decoupled anchor-free head to YOLOv7 is the label assigner. YOLOv7 and YOLOX uses SimOTA as its default label assigner. However, Li et al. (2022) YOLOv6 uses Task-aligned Assigner (TAL) for its label assigner. They reported that TAL performs better than SimOTA. Therefore, in applying decoupled anchor-free head, it might be better to use TAL as label assigner.

3.2.7 Partitioning Image

Partitioning the image has the potential to improve the accuracy of small object detection. By partitioning images into multiple smaller images like shown in Figure 3.6, the down scaling factor of image to neural network input size is reduced, thereby reducing the loss of information. This approach allows the network to retain finer details and preserve the integrity of small objects, ultimately leading to more accurate detection results.

One challenge associated with partitioning image is the increase in inference latency. When an image is partitioned into multiple sections, the neural network needs to perform separate detections on each partition. As a result, the total inference time is multiplied by the number of partitions. For instance, if we divide an image into four parts, the network will have



Prediction for Classes and Boxes are decoupled unlike original YOLO head

Figure 3.5: Decoupled Anchor-free Head

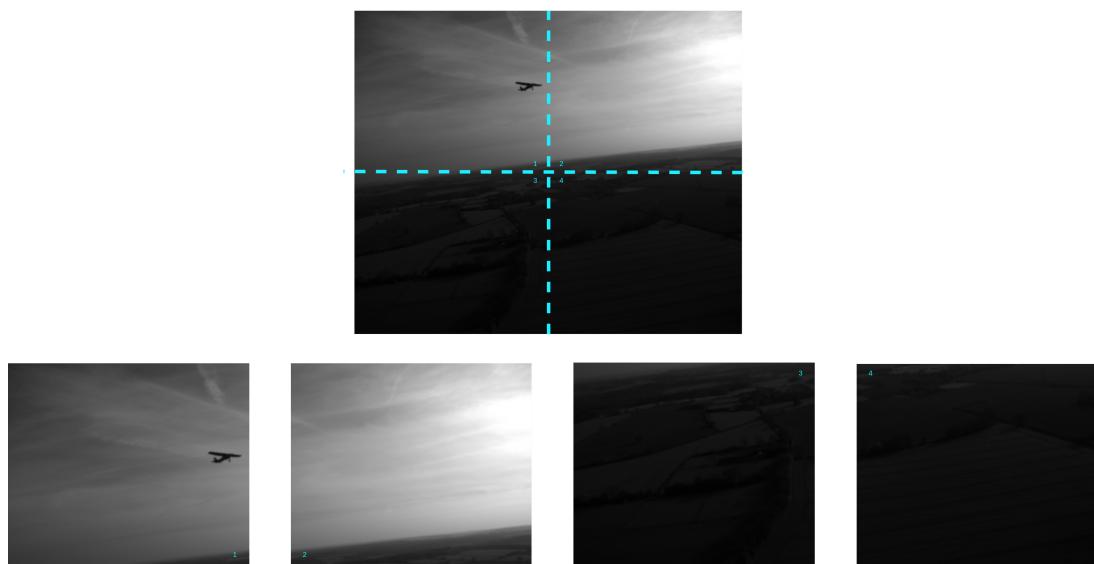


Figure 3.6: An Image Partitioned to 4 Images

to carry out four separate detections, leading to a significant increase in latency. Therefore, it is important to find the correct balance between the number of partition, and network input size.

3.3 Computational Resource

To conduct this research, we will be using a computer with the specification shown in Table 3.1.

Table 3.1: Computer Specification

Components	Specification
CPU	Intel® Core™ i5-9400F CPU @ 2.90GHz
GPU	Nvidia Geforce RTX 2080 Ti
	Memory 12 GB
	CUDA CC 7.5
RAM	12 GB
Disk Available Memory	1.3 TB
Operating System	Ubuntu 20.04
CUDA Toolkit Version	11.7
Pytorch Version	1.13.1

3.4 Pilot Test

To ensure the reliability of the computational resource, and to find the resource-induced constraint, we performed A pilot test. In this pilot test, we trained several YOLOv7 models with varying input sizes on 400 images from dummy dataset for 300 epochs. The dummy dataset have the same dimension as the “Airborne Object Tracking Dataset” (2021). The results are presented in Table 3.2.

From Table 3.2, we want to pick a baseline model to apply our modification. Since we want to persist the features of the 2048×2448 px images as much as possible, we want to pick a model that has the largest input size but still able to give enough for some changes in

Table 3.2: Pilot Test Training

No	Model	Input Size	Training Time (300 epochs)	VRAM Usage	Average GPU Temperature
0	YOLOv7	640	4.0h	4.5GB	82
1	YOLOv7 batch-size=2	640	2.5h	6.5GB	82
2	YOLOv7	960	4.7h	6.5GB	84
3	YOLOv7	1600	20h	9.0GB	84
3	YOLOv7 batch-size=2	1600	20h	Out of Memory	85
4	YOLOv7	2000	N/A	Out of Memory	N/A
5	YOLOv7-w6	1600	N/A	10GB	85
6	YOLOv7-d6	1600	N/A	Out of Memory	N/A
7	YOLOv7-e6	1600	N/A	Out of Memory	N/A
8	YOLOv7-e6e	1600	N/A	Out of Memory	N/A

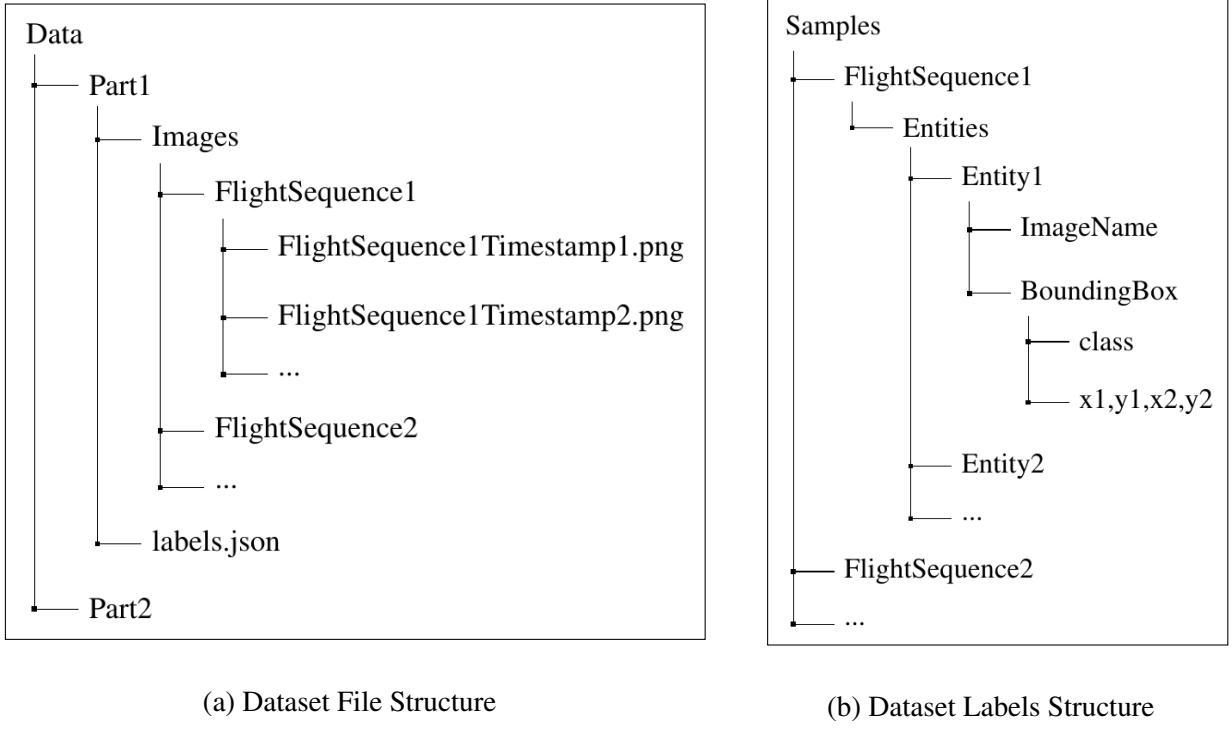


Figure 3.7: File Structure and Label Structure of “Airborne Object Tracking Dataset” (2021)

architecture. For this reason, we picked YOLOv7 (entry number 3) with input size 1600 and batch size 1 as the baseline. This model can be trained in a reasonable time (20 hours) and enough spare room in the VRAM for architecture modifications.

3.5 Dataset Preparation

The overview of the dataset that will be used in experiment and the procedure of preparing the data for experiment are shown in this section.

3.5.1 Dataset Source

Dataset containing annotated images of airborne objects can be obtained from “Airborne Object Tracking Dataset” (2021) that was hosted in an AWS S3 Bucket. The dataset consist of several Unmanned Aerial Vehicle (UAV) flights’ frame-by-frame camera capture. The dataset images is structured like the file tree shown in Figure ???. For the labels, it is stored in a JSON file `labels.json` on each part of the data. The label JSON structure is shown in Figure ???.

Notice that the labels are structured in an entity based manner. This made the label conversion process more complex. Handling this labelling structure will be discussed more in the next section.

Dataset Statistics

There are 7 classes in the dataset, but there are 3 dominating classes. The size of the dataset and its class distribution can be seen on Table 3.3 and 3.4. In total, the dataset is a 13.4 TB images of 3.39 million objects.

If we look at the area (in px) distribution of the objects’ bounding boxes, we will find the

Table 3.3: Original Dataset Splits

Splits	Size (TB)	UAV Flight Sequences	Total Images	Total Labels
Training	11,3	4154	4975765	2891891
Validation + Test	2.1	789	943852	496075
Total	13,4	4943	5919617	3387966

Table 3.4: Dataset Objects' Classes Distribution

Splits	Total Objects	Airplane	Helicopter	Bird	<i>Other 4 Classes</i>
Training	2,89 M	0,79 M	1,22 M	0,33 M	0,54 M
Validation + Test	0,50 M	0,13 M	0,17 M	0,06 M	0,14 M
Total	3,39 M	0,92 M	1,39 M	0,39 M	0,69 M

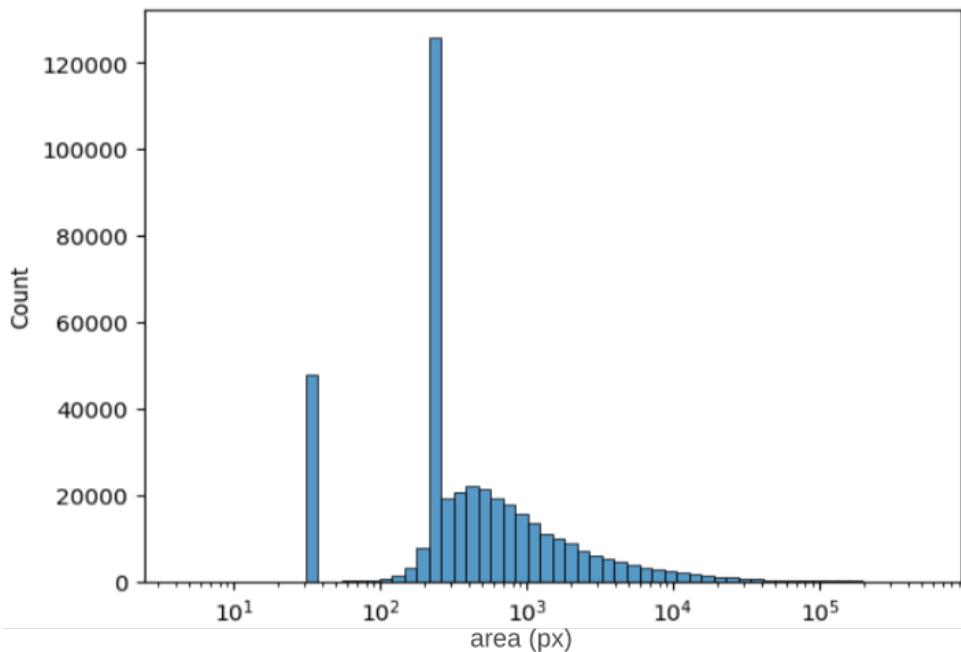


Figure 3.8: Distribution of Bounding Boxes' Area

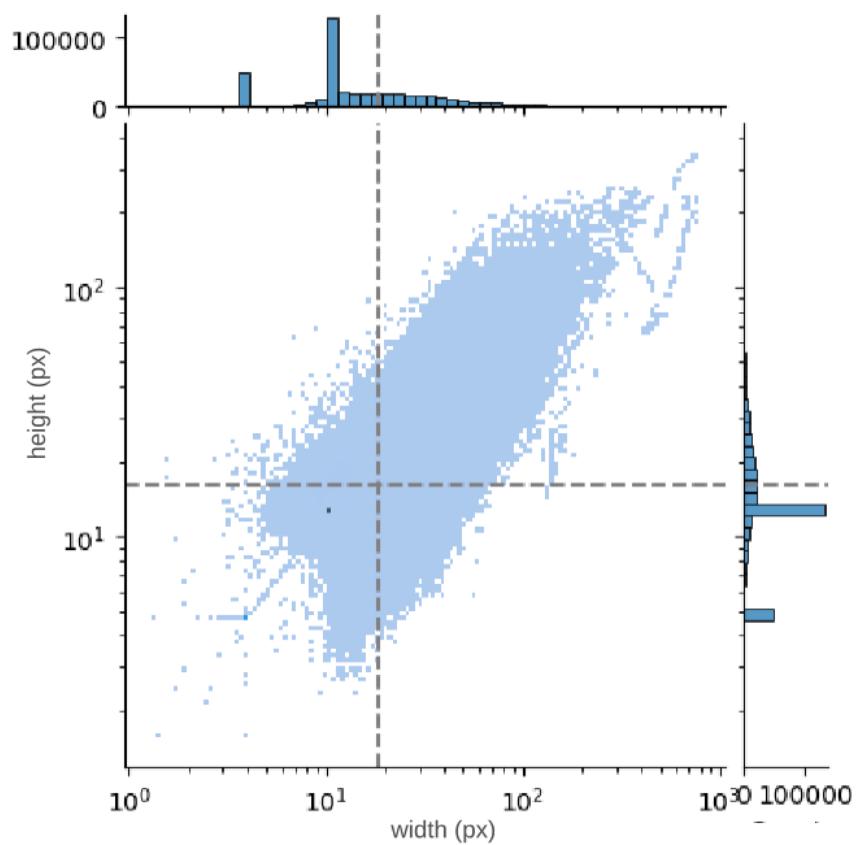
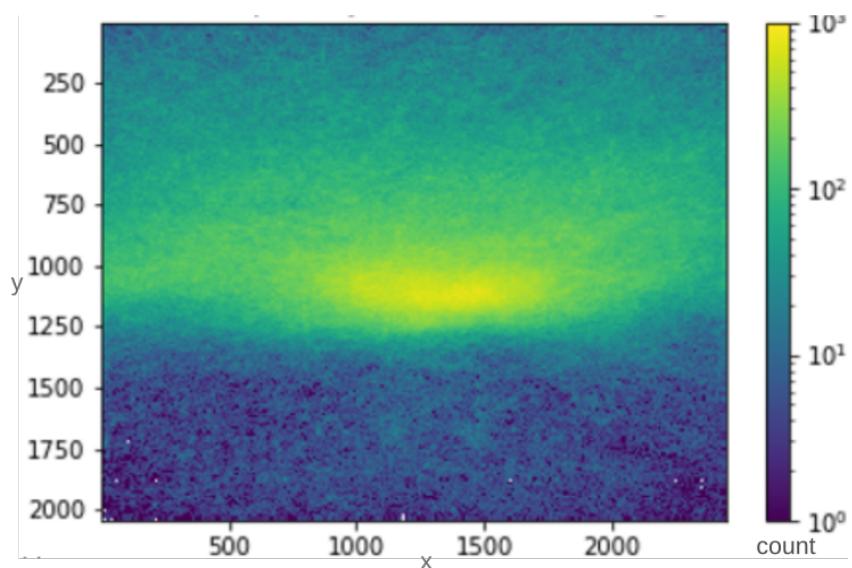


Figure 3.9: Distribution of Bounding Boxes' Widths and Heights



Source: “Airborne Object Tracking Dataset” (2021) under CDLA-Permissive 1.0

Figure 3.10: Distribution of Objects’ Position

Table 3.5: Dataset Sampling Distribution

Splits	Total Images	Classes Percentage				
		Airplane	Helicopter	Bird	Drone	Negative
Training	400	23.75%	23.75%	23.75%	23.75%	5%
Validation	100	20%	20%	20%	20%	20%
Test	200	20%	20%	20%	20%	20%

histogram in Figure 3.8. Take note that in the figure, the x-axis is using in logarithmic scale, which means the true data is very right skewed. The median of the areas is $314px$, while the 5th and 95th percentile are $36px$ and $5061px$, three orders of magnitude difference.

The widths and heights of the objects themselves are distributed in a way shown in Figure 3.9: The figure uses logarithmic scale for x and y, and the dashed lines represent the median for x and y axis. Meanwhile, The distribution of objects position in the camera can be seen on Figure 3.10. We can see that most of the objects are around the center of the image.

3.5.2 Dataset Sampling

This subsection will show how the dataset is sampled and prepared for experient.

Sampling Distribution

As discussed in section 3.5.1, The size of the dataset is massive. For this reason, we only downloaded the planned encounters from the AWS S3 Bucket which in total amounted to 1.1 TB. As this number is still too large due to the limitation of computational resource, we will only sample some of them for training and testing. We will sample in total 700 images from the dataset with splits as shown in Table 3.5.

Sampling and Label Conversion Procedure

Sampling the dataset was not straightforward. Due to how the “Airborne Object Tracking Dataset” (2021) files and labels was structured, we had to make a sampling and converting procedure like the following:

1. Open all `labels.json` file and load all entities into a single list called `entities`
2. Let `Img2Boxes` be a dictionary with image names as key and list of bounding boxes in the image as value.
3. Let `Clss2Img` be a dictionary with 4 class names as key (airplane, bird, etc) and set of image name that contain object of those classes as the value.
4. Populate `Img2Boxes` and `Clss2Img` in the following manner:

```

1  For entity in entities:
2      Img2Boxes[entity.ImageName].append(entity.BoundingBox)
3      Clss2Img[entity.BoundingBox.class].append(entity.ImageName)

```

5. Calculate the total image needed for each class according to Table 3.5.
e.g. Total image needed for airplane class is $\frac{400 \times 23.75 + 100 \times 20 + 200 \times 20}{100}$.

6. Distribute the images to train, valid and test.

```
1  For class in list_of_classes:  
2      Images[class] = Cls2Img[class].random_choice(TotalImageNeeded[←  
         class])  
3  
4  For class in list_of_classes[-1]: // except negative sample  
5      addtotrain = images[class][:23.75/63.75*TotalImageNeeded[class]]  
6      images[class] = images[class][23.75/63.75*TotalImageNeeded[class]←  
         :]  
7      train.append(addtotrain)  
8  
9  do the same to valid and test  
10 process the negative sample independently
```

7. Convert `train, valid, test` to darknet format.

```
1  For img in train:  
2      label = []  
3      For boxes in Img2Boxes[img]  
4          // to_darknet converts class xyxy to class x y w h normalized  
5          label.append(to_darknet(boxes.BoundingBox))  
6  
7      copy(img, train_folder+img)  
8      write(label, train_folder+img.with_suffix('.txt'))  
9  
10 repeat this for valid and test
```

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CHAPTER IV

EXPERIMENTS

4.1 Baseline Performance

For comparison purposes, we first measure the baseline performance of YOLOv7 with all modification candidates from section 3.2 stripped. We call this model as **YOLOv7-plain**. After 300 epochs of training with batch-size 1 like in the experiment setup, we found that this model was unable to detect anything on the test set (a valid detection is detection with $IoU > 0.5$ to groundtruth).

4.2 Mosaic Augmentation and Anchor Recalculation

In this section, we present the effect of mosaic augmentation and anchor recalculations on the *mAP@50* score when applied independently and combinatively. For comparison purposes, we assigned names the models as **YOLOv7-M**, **YOLOv7-AR**, and **YOLOv7-MAR**. These names correspond to **YOLOv7-plain** with mosaic augmentation, **YOLOv7-plain** with anchor recalculations, and **YOLOv7-plain** with both mosaic augmentation and anchor recalculations, respectively.

The process of applying mosaic augmentation to the dataset is pretty straightforward as YOLOv7's implementation code already provide the mosaic augmentation tool. A mosaic augmentation result example can be seen in Figure 4.1. Four images with the labels in numeric form is combined and resized.

Anchor recalculations is done by clustering the training data's widths and heights to 9 centroid using k-means algorithm. However, due to the skewed distribution of the dataset, regular k-means (with L^2 Distance) actually failed to form 9 clusters. To fix this, we used a distance function

$$L = \sqrt{\ln^2 \frac{w_1}{w_2} + \ln^2 \frac{h_1}{h_2}} \quad (4.1)$$

Distance function in equation 4.1 was actually an L^2 distance but with log-transformed space. With this function, k-means was finally able to cluster the data into 9 centroids. These centroids are used by the head layers as anchors. Each head uses 3. The comparison of the original anchor and recalculated anchor can be seen in Table 4.1 and Figure 4.2.

If we observe the distribution of anchors before and after recalculations in Figure 4.2, we can see that indeed the recalculated anchors cover more of the dataset than the original. 8 out

Table 4.1: Anchor Points Before and After Recalculations

Head	Original Anchors	Recalculated Anchors
1	[12,16], [19,36], [40,28]	[4,4], [14,5], [11,11]
2	[36,75], [76,55], [72,146]	[27,8], [18,17], [41,14]
3	[142,110], [192,243], [459,401]	[43,32], [86,27], [149,70]

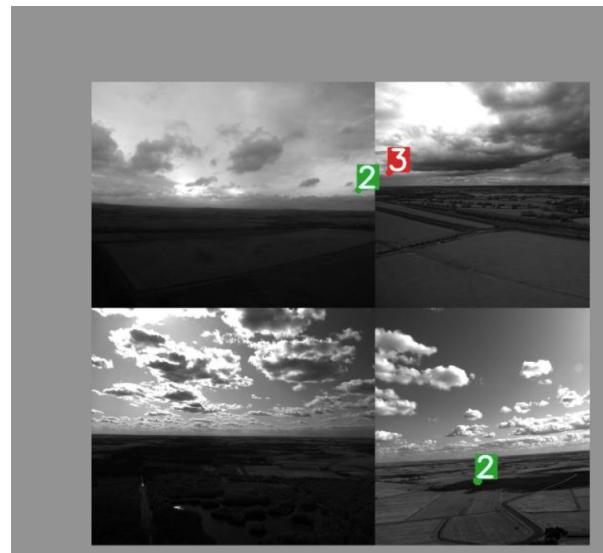


Figure 4.1: An example of mosaic augmented image

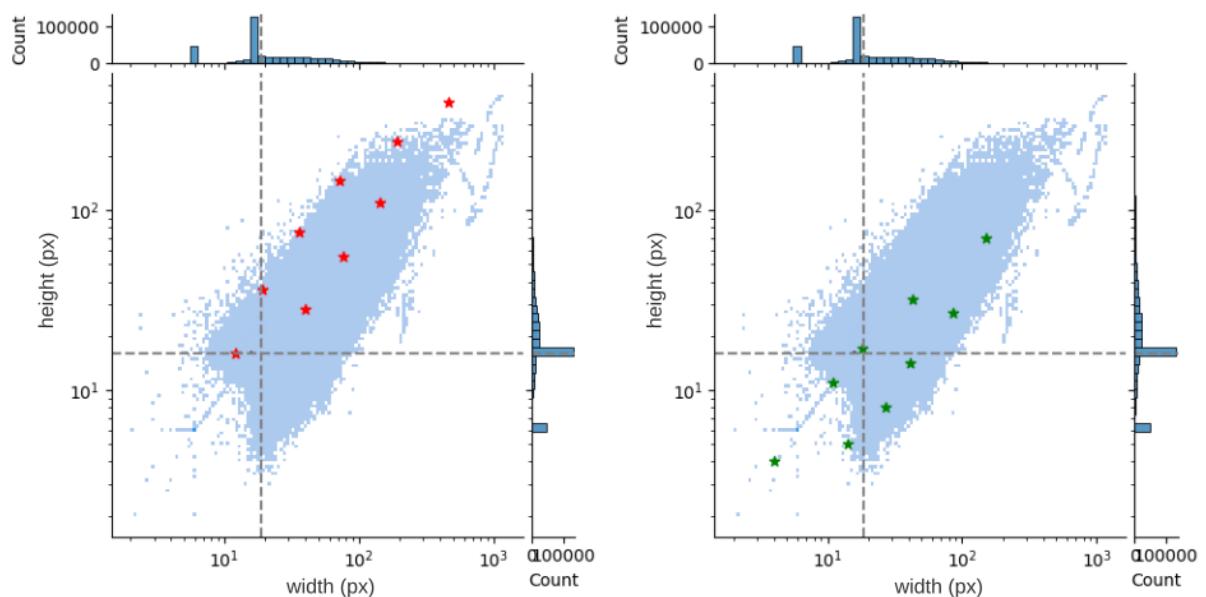


Figure 4.2: Anchor Distribution on Dataset. Left: Original Anchor. Right: Recalculated Anchors

Table 4.2: Mosaic Augmentation and Anchor Recalculation Performance

No	Model	mAP@50
0	YOLOv7-plain	0%
1	YOLOv7-M	0%
2	YOLOv7-AR	0%
3	YOLOv7-MAR	11.2%
	Improvement	+11.2%

of 9 of the original anchors are placed in the first quadrant of the median axis. It means that those 8 anchors are responsible for only 25% of the dataset and leave the rest to 1 anchor. This is very inefficient. In contrast, the recalculated anchors have a more balanced distribution with anchors distributed across each quadrant.

Performance

The performance of the three models, namely YOLOv7-M, YOLOv7-AR, and YOLOv7-MAR, was compared to that of the baseline model YOLOv7-plain. The results are presented in Table 4.2. It can be observed from the table that YOLOv7-plain alone was unable to detect any objects in the test set. However, after applying both mosaic augmentation and anchor recalculation, the model achieved a notable improvement with a score of 11.2% at mAP@50.

Since the model YOLOv7-MAR was the only model that was capable of detection in the test set, we henceforth establish this model as the baseline for further modification. Meaning, in the subsequent sections, any modifications mentioned should be presumed to be composed of mosaic augmentation and anchor recalculation, in addition to the respective modification that was applied, unless explicitly stated otherwise.

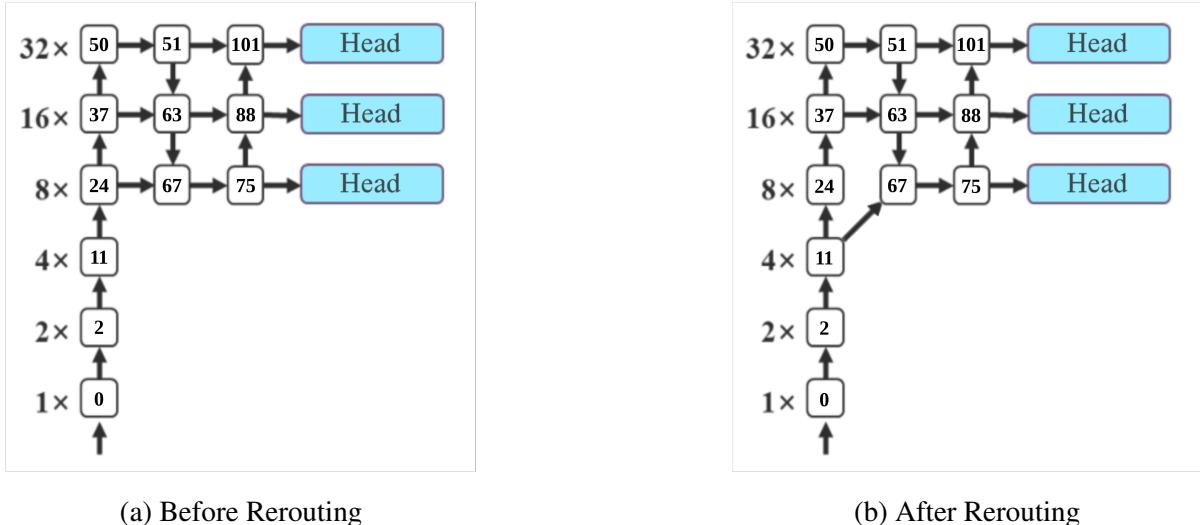
4.3 Replacing Localization Loss to EIoU

In this section, we experimented with *EIoU*. We replaced the original *CIoU* loss of YOLOv7 to pure *EIoU* and convexified version of *EIoU*. The convexication was done by modifying the *EIoU* loss from $-EIoU$ to $(1 - EIoU)^2$ for better gradient dynamics during training. The performance of these modifications can be seen in Table 4.3

Surprisingly, although *EIoU* outperformed *CIoU* when applied to networks like Faster-RCNN+ResNet and RetinaNet as Peng and Yu (2021) claimed, it performed worse when applied to YOLOv7 with “Airborne Object Tracking Dataset” (2021). Even after convexication, *CIoU* still outperform *EIoU* by 6.28%.

Table 4.3: EIoU Localization Loss Performance

No	Modification	mAP@50
0	YOLOv7-MAR +CIoU (original)	11.2%
1	YOLOv7-MAR + EIoU	0%
2	YOLOv7-MAR + EIoU + Convexication	4.92%
	Improvement	-6.28%



Adapted from: C.-Y. Wang, Bochkovskiy, et al. (2022) with permission (see Appendix C)

Figure 4.3: Modifying Connection to Earlier Feature Map Stage

Table 4.4: Performance of The Rerouted Model

No	Modification	mAP@50
0	YOLOv7-MAR	11.2%
1	YOLOv7-MAR + rerouting	14.09%
	Improvement	+2.98%

4.4 Utilizing Earlier Feature Map Stage

For this modification, we reconfigured the source of the feature map by redirecting it from P3 to P2, as shown in Figure 4.3. Specifically, we adjusted the routing on layer 66, changing it from 24 to 11. Since the output of layer 11 is at a different scale compared to 24 (with a scaling factor of 2^{-2} and 2^{-3} respectively), we modified the upsampling factor of layer 55 from 2 to 4 to ensure size compatibility with layer 11. However, this change in upsampling disrupted the subsequent layers. To solve this, we performed downsampling after layer 75 (connected to the head) by setting layer 77's stride to 2 and layer 79's stride to 4, resolving the size mismatch in the subsequent layers. The complete configuration of the layers can be seen in the appendix.

As presented in Table 4.4, rerouting the source of feature map to an earlier stage produce an improvement of 2.98% compared to YOLOv7-MAR.

4.5 Additional YOLO Detection Head

To add additional head layer, we utilized the feature map at the P2 scale of the network. We introduced an upsampling block after layer 75 and fused it with layer 11 at layer 79 by concatenation. To maintain the continuity of the network, we introduced a downsampling block that concludes at layer 87. The subsequent layers in the network retained their original structure, but with layer numbering shifted by 25 as seen on Figure 4.4.

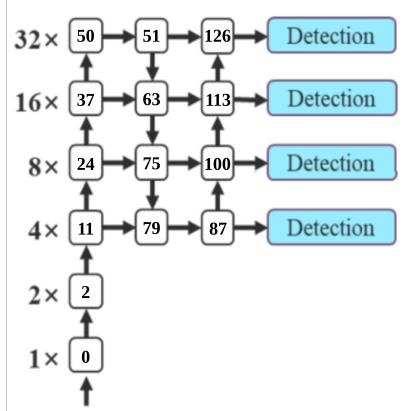


Figure 4.4: Model Architecture After Increasing The Head

Table 4.5: Additional Head Performance

No	Modification	mAP@50
0	YOLOv7-MAR	11.2%
1	YOLOv7-MAR + more head	5.19%
	Improvement	-6%

As depicted in Table 4.5, additional head layer hurt the performance of the model. This is counterintuitive. We had seen P2 feature map capable of increasing the mAP in previous section. If we look at the loss at validation set, we can see that YOLO-MAR + head is minimizing the localization loss more than YOLO-MAR + rerouting. There are several reasons we thought of why this happened:

1. The network was simply producing loose bounding boxes prediction which looks better in loss function but fail when threshold criteria like in *mAP@50* is introduced.
2. This is an effect of bad choice of hyperparameters.

4.6 Decoupled Anchor-free Head

We experimented with replacing the coupled YOLO head to of a decoupled anchor-free head. Upon replacing the head, we also replaced the label assigner from SimOTA to TAL. The performance of this modification is shown in Table 4.6.

The model was initially unable to converge due to numerical instability caused by having the objects becoming too small upon downscaling. After stabilizing the loss function to handle these cases as shown in Appendix B, this modification was able to improve the mAP score by 21.78%.

4.7 Partitioning Image

We trained the models using partitioned image of the original dataset. In inference, we expect to partition an image into 4 equal sized images, which will then be fed to the neural

Table 4.6: Anchor-free Head Performance

No	Model	mAP@50
0	YOLOv7-MAR (anchor head)	11.2%
1	YOLOv7-MAR + anchor-free head	0%
1	YOLOv7-MAR + anchor-free head *numerically stabilized	32.98%
	Improvement	+21.78%



Figure 4.5: Example Image Source for Cropping



(a) Object Only Partially Present
in Crop Area

(b) Object Not Present in Crop
Area

(c) Crop Area Out Of Image
Boundary

Figure 4.6: Cropping without Strategy (Random Center)

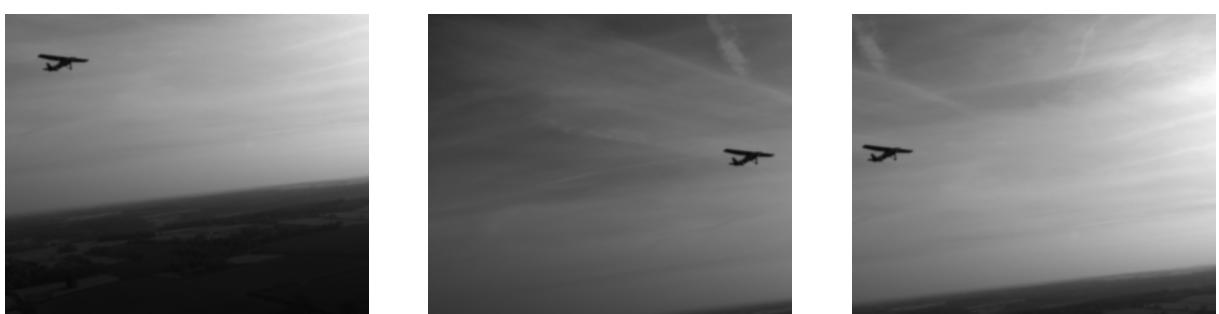


Figure 4.7: Cropping with Strategy

network. This way, the network will produce 4 independent output that we can combine to form the final inference.

To generate partitioned data for training, we cropped image with size of $(W/2, H/2)$ based on the location of the objects bounding boxes. Therefore, it can be guaranteed that each image has at least an object except for negative class images. The procedure for this is described in the following:

1. Open all images and their labels which consist of list of objects in it.

2. For each object in an image, define a crop area with the following way:

(a) First, define the width and height of crop as a vector $\overrightarrow{crop_{wh}}$

(b) Then, we wanted to find a lower bound and upper bound for the x and y value that the crop center can be placed such that it would not cut object bounding box and not out of the boundary of the image itself. For example, for cropping the image in Figure 4.5, we wanted to ensure the result would not be like in Figure 4.6. So, for the lower bound, we have:

$$\overrightarrow{crop_{lb}} = \max\left(\frac{\overrightarrow{c_{wh}}}{2} - \frac{\overrightarrow{crop_{wh}}}{2}, \frac{\overrightarrow{crop_{wh}}}{2} - \overrightarrow{c_{xy}}\right) \quad (4.2)$$

Where c_{wh} = the width and height of the object's bounding box

c_{xy} = the center of the object's bounding box

$$\max(\vec{a}, \vec{b}) = \begin{pmatrix} \max(a.x, b.x) \\ \max(a.y, b.y) \end{pmatrix}$$

And for the upper bound:

$$\overrightarrow{crop_{ub}} = \max\left(\frac{\overrightarrow{c_{wh}}}{2} - \frac{\overrightarrow{crop_{wh}}}{2}, 1 - \frac{\overrightarrow{crop_{wh}}}{2} - \overrightarrow{c_{xy}}\right) \quad (4.3)$$

(c) Finally, Equation 4.2 and 4.3 can be used to compute a randomized but constrained center point of the crop area by combining them to the following equation:

$$\overrightarrow{crop_{xy}} = \text{diag}(R)(\overrightarrow{crop_{ub}} - \overrightarrow{crop_{lb}}) + \overrightarrow{crop_{lb}} + \overrightarrow{c_{xy}} \quad (4.4)$$

Where R = a random vector with value of its element is within $(0, 1)$

$\text{diag}(R)$ = a function that convert a vector R to a diagonal matrix with elements of R as its diagonal

3. After the cropping area has been defined, the bounding boxes' values must also be con-

verted to the cropped perspective. These conversions were done like the following:

$$\hat{\vec{c}}_{xy} = \vec{c}_{xy} - (\vec{crop}_{xy} - \frac{\vec{crop}_{wh}}{2}) \quad (4.5)$$

$$\hat{\vec{c}}_{wh} = \frac{\vec{c}_{wh}}{\vec{crop}_{wh}} \quad (4.6)$$

Where the division operation in Equation 4.6 is an element-wise division, meaning the x component of the numerator is divided by the x component of the denominator, likewise for y component.

By following this procedure, it is ensured that the cropping for training image would be like in Figure 4.7 and not like Figure 4.6. Without using this strategy, the resulting partitioned image for training would have a significant increase in negative class that could reduce the neural network recall ability.

The procedure so far only consider for the case when the objects are about $crop_{wh}$ away from each other. If the objects are within $crop_{wh}$ from each other, we redefined the c_{xy} and c_{wh} to be the smallest box that bounds every object in the image. Redefinition is done in the following way:

Let $B = \text{set bounding boxes in an image}$

$$c_{tl}.x = \min \{c_{tl}^*.x : \forall c^* \in B\}$$

$$c_{tl}.y = \min \{c_{tl}^*.y : \forall c^* \in B\}$$

$$c_{br}.x = \max \{c_{br}^*.x : \forall c^* \in B\}$$

$$c_{br}.y = \max \{c_{br}^*.y : \forall c^* \in B\}$$

$$\vec{c}_{xy} = \frac{\vec{c}_{br} + \vec{c}_{tl}}{2} \quad (4.7)$$

$$\vec{c}_{wh} = \vec{c}_{br} - \vec{c}_{tl} \quad (4.8)$$

Since the image were partitioned to a smaller size, we were finally able to use a smaller input size for the neural network. We experimented by using 640 and 960 input size on some previous modifications. The performance is shown on Table 4.7. YOLOv7-MAR + anchor-free with input size 960 produced the greatest mAP@50 score amongst other model when partitioned to 4.

Table 4.7: Partitioning Image Performance

No	Model	Input Size	Partition4 mAP@50
0	YOLOv7-AR	960	2.9%
1	YOLOv7-MAR	640	18.46%
3	YOLOv7-MAR	960	37.69%
4	YOLOv7-MAR + rerouting	960	30.04%
5	YOLOv7-MAR + more head	960	10.53%
6	YOLOv7-M + anchor-free	640	37.57%
7	YOLOv7-M + anchor-free	960	46.18%

Table 4.8: Inference Speed of Modified Models

No	Model	Input Size	Inference Speed	
			YOLOR Reparameterized	
0	YOLOv7-MAR, plain, M, AR, EIoU	1600	29.6 FPS	29.6 FPS
1	YOLOv7-MAR + rerouting	1600	24.28 FPS	24.65 FPS
2	YOLOv7-MAR + more head	1600	24.15 FPS	25.01 FPS
3	YOLOv7-MAR + anchor-free	1600	26.42 FPS	26.01 FPS
4	YOLOv7-MAR	Partition 4, 960	72.45 FPS	73.75 FPS
5	YOLOv7-MAR + rerouting	Partition 4, 960	61.35 FPS	62.64 FPS
6	YOLOv7-MAR + more head	Partition 4, 960	60.64 FPS	61.64 FPS
7	YOLOv7-M + anchor-free	Partition 4, 960	63.17 FPS	64.2 FPS
8	YOLOv7-MAR	Partition 4, 640	69.75 FPS	71.78 FPS
9	YOLOv7-MAR + rerouting	Partition 4, 640	73.61 FPS	74.73 FPS
10	YOLOv7-MAR + more head	Partition 4, 640	60.84 FPS	60.92 FPS
11	YOLOv7-M + anchor-free	Partition 4, 640	65.29 FPS	65.34 FPS

Table 4.9: Floating Point Operations For a Single Inference

No	Model	Input Size	GFLOPs ($\tilde{MAC} \times 2$)
0	YOLOv7-MAR, plain, M, AR, EIoU	1600	552.11
1	YOLOv7-MAR + rerouting	1600	692.02
2	YOLOv7-MAR + more head	1600	627.25
3	YOLOv7-MAR + anchor-free	1600	1374.47
4	YOLOv7-MAR, plain, M, AR, EIoU	960	205.07
5	YOLOv7-MAR + rerouting	960	257.03
6	YOLOv7-MAR + more head	960	232.98
7	YOLOv7-M + anchor-free	960	510.53
8	YOLOv7-MAR	640	89.39
9	YOLOv7-MAR + rerouting	640	112.04
10	YOLOv7-MAR + more head	640	101.55
11	YOLOv7-M + anchor-free	640	222.53

4.8 Latency

In this section, the latency of the modifications that involved architectural changes is presented. The data obtained using computer with specification presented in section 3.3. Table 4.8 shows that all the partition 4 models have > 40 FPS inference speed. This means that they are able to perform at > 10 FPS even without batching to detect a full image, making them all valid candidate for the best model.

As additional information, the total floating point operations (FLOPs) for each architecture modification can be seen in Table 4.9. The values are calculated using THOP profiling tool in a hardware with Fused Multiply Addition (FMA) instructions, thus it counted Multiply-Accumulate (MAC) instead of the true FLOPs. Therefore, to find the FLOPs, output of THOP must be multiplied by 2 ($FLOPs = MAC \times 2$).

4.9 Model Selection



Figure 4.8: Example Prediction Result of The Selected Best Model

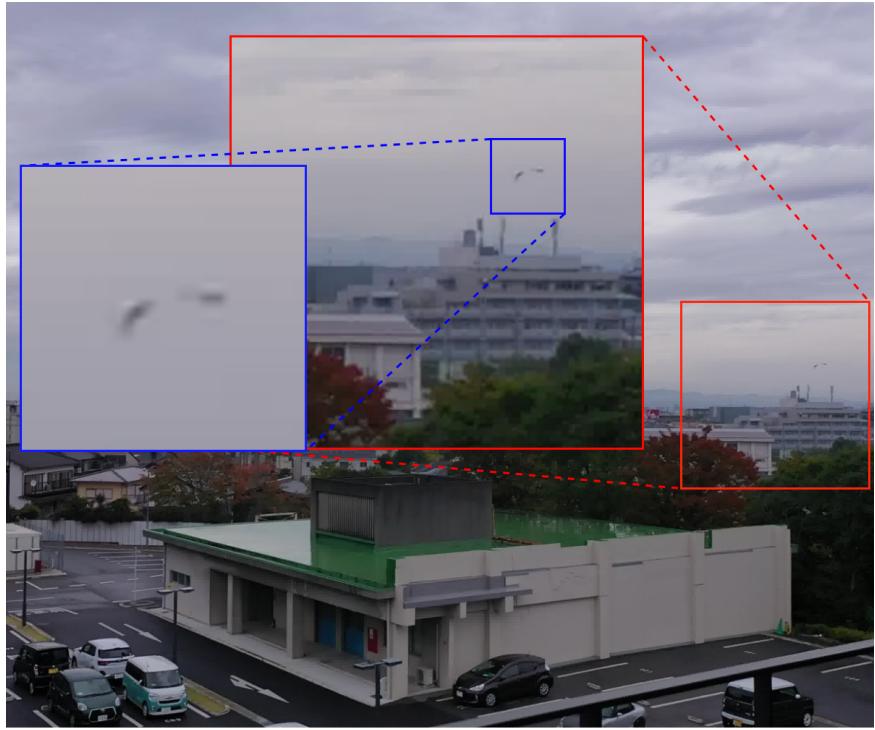
Since all the modified models qualify for model selection as shown in Table 4.8, we only have to pick the model that has the largest mAP. From Table 4.2, 4.3, 4.4, 4.5, 4.6, and 4.7, we found that YOLOv7-M + anchor-free + Partition4 with input size 960 to have the largest mAP score that is 46.18%.

An example of detection result from this model can be seen on Figure 4.8. As shown in the figure, the model was able to localize and classify the helicopter when it was still very far away.

4.10 Exploratory Analysis: Low Resolution/Pixel Density Images

The dataset we used to train and benchmark so far have 2048×2448 resolution. This means that it is highly probable that the small objects are recognizable if we zoom in the image. But what about objects that are not recognizable even after zooming? In this section, we would like to experiment with low resolution or low pixel density input. The purpose of this experiment is to find out the performance of the selected best modified YOLOv7 models against bad quality image. We want to find out its ability to predict vague looking objects.

For the experiment, we purposely select 50 images from Kondo et al. (2023) with airborne objects that are hard to recognize the shape even after zooming. These images will first converted into grayscale to make it similar with the training dataset that was obtained from “Airborne Object Tracking Dataset” (2021). Kondo et al. (2023) images quality are different compared to “Airborne Object Tracking Dataset” (2021). Although it has higher pixel resolution ($\sim 3000 \times 2000$), Kondo et al. (2023) images’ pixel density is subpar compared to “Airborne Object Tracking Dataset” (2021). Kondo et al. (2023) has 136.6 *ppi* pixel density while “Airborne



Source: Kondo et al. (2023), permissible under copyright license (see Appendix C)

Figure 4.9: Example Low Pixel Density Image in Kondo et al. (2023)

Object Tracking Dataset” (2021) has 187.4 *ppi*. Observe Figure 4.9, the object is almost not recognizable even after zooming due to low pixel density, different from Figure 1.1 introduced in section 1.1.

After running these low pixel density images with the best modified YOLOv7 model, we found that the model was unable to correctly detect the airborne objects in them ($mAP = 0\%$). The model did not detect any airborne objects on most images. On some rare cases, the model was able to localize the airborne object but unable to classify it to the proper class. One example for such cases is the image in Figure 4.9. The model was able to localize the birds properly, but classify them as airplane. We also tried to crop the images so that it would have the same resolution as “Airborne Object Tracking Dataset” (2021), but the result remain the same.

This experiment is an evidence that the model was unable to perform inference on low detail quality image. However, this outcome might be caused by the training data significantly different to Kondo et al. (2023) rather than the fault of the model itself. The model was trained on dataset where all the images was taken from the same or similar camera that produce high pixel density images. It is possible that inclusion of bad quality image in the dataset would improve the model ability to perform detection on low pixel density images.

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CHAPTER V

CONCLUSION

5.1 Conclusion

Based on the experiments conducted in previous chapter, it can be observed that some specific modification can improve YOLOv7 ability on detecting airborne objects, while others have negligible or even negative effect. In conclusion, we found that:

1. YOLOv7 was only able to perform detection on airborne objects after adding mosaic augmentation to the training data and recalculated its anchor to fit the data. This modification improved the mAP score from 0 to 11.2%.
2. EIoU, even with its convexification technique, was not able to outperform YOLOv7's original CIoU. It produced only 4.92% in mAP score.
3. Rerouting the detection to use an earlier stage of feature map can improve slightly improve the mAP.
4. Additional head on YOLOv7 did not perform better than original 3 head.
5. Replacing head to a decoupled anchor free head greatly improve the detection capability.
6. Applying image partition to all model greatly improve their detection performance. The greatest performance after applying image partition came from anchor-free head modification which produced 46.18% mAP, a 13.2% improvement compared to without partition.

Amongst all the proposed modifications applied to YOLOv7, we also found that applying image partition, and replacing head to a decoupled anchor free head performed the best on detecting airborne objects, while still able to perform inference in real-time.

With this, we have explored different ways to improve the detection of airborne objects with YOLOv7. However, there are still more things we can try in the future to make it even better. One idea is to use attention mechanisms, which help the model focus on important features related to airborne objects. We could also investigate transfer learning and domain adaptation to leverage existing knowledge and adapt the model to specific situations. To handle low pixel density data, we could introduce subpixel convolutions instead of pyramid upsampling when increasing the dimension of features. Overall, there are still many opportunities for further research and enhancements that could be done in optimizing YOLOv7 airborne object detection.

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APPENDIX A

YOLOv7 + more head Architecture Configuration

```
1 # parameters
2 nc: 4 # number of classes
3 depth_multiple: 1.0 # model depth multiple
4 width_multiple: 1.0 # layer channel multiple
5
6 # anchors
7 anchors:
8   # [12,16, 19,36, 40,28] # P3/8
9   # [36,75, 76,55, 72,146] # P4/16
10  # [142,110, 192,243, 459,401] # P5/32
11  - [4,4, 10,10, 23,8]
12  - [16,15, 41,11, 59,23]
13  - [46,34, 47,41, 85,29]
14  - [114,27, 112,62, 272,71]
15
16 # yolov7 backbone
17 backbone:
18   # [from, number, module, args]
19   [[-1, 1, Conv, [32, 3, 1]], # 0
20
21   [-1, 1, Conv, [64, 3, 2]], # 1-P1/2
22   [-1, 1, Conv, [64, 3, 1]],
23
24   [-1, 1, Conv, [128, 3, 2]], # 3-P2/4
25   [-1, 1, Conv, [64, 1, 1]],
26   [-2, 1, Conv, [64, 1, 1]],
27   [-1, 1, Conv, [64, 3, 1]],
28   [-1, 1, Conv, [64, 3, 1]],
29   [-1, 1, Conv, [64, 3, 1]],
30   [-1, 1, Conv, [64, 3, 1]],
31   [[-1, -3, -5, -6], 1, Concat, [1]],
32   [-1, 1, Conv, [256, 1, 1]], # 11
33
34   [-1, 1, MP, []],
35   [-1, 1, Conv, [128, 1, 1]],
36   [-3, 1, Conv, [128, 1, 1]],
37   [-1, 1, Conv, [128, 3, 2]],
38   [[-1, -3], 1, Concat, [1]], # 16-P3/8
39   [-1, 1, Conv, [128, 1, 1]],
40   [-2, 1, Conv, [128, 1, 1]],
41   [-1, 1, Conv, [128, 3, 1]],
42   [-1, 1, Conv, [128, 3, 1]],
43   [-1, 1, Conv, [128, 3, 1]],
44   [-1, 1, Conv, [128, 3, 1]],
45   [[-1, -3, -5, -6], 1, Concat, [1]],
46   [-1, 1, Conv, [512, 1, 1]], # 24
47
48   [-1, 1, MP, []],
49   [-1, 1, Conv, [256, 1, 1]],
```

```

50 [-3, 1, Conv, [256, 1, 1]],  

51 [-1, 1, Conv, [256, 3, 2]],  

52 [[[-1, -3], 1, Concat, [1]], # 29-P4/16  

53 [-1, 1, Conv, [256, 1, 1]],  

54 [-2, 1, Conv, [256, 1, 1]],  

55 [-1, 1, Conv, [256, 3, 1]],  

56 [-1, 1, Conv, [256, 3, 1]],  

57 [-1, 1, Conv, [256, 3, 1]],  

58 [-1, 1, Conv, [256, 3, 1]],  

59 [[[-1, -3, -5, -6], 1, Concat, [1]],  

60 [-1, 1, Conv, [1024, 1, 1]], # 37  

61  

62 [-1, 1, MP, []],  

63 [-1, 1, Conv, [512, 1, 1]],  

64 [-3, 1, Conv, [512, 1, 1]],  

65 [-1, 1, Conv, [512, 3, 2]],  

66 [[[-1, -3], 1, Concat, [1]], # 42-P5/32  

67 [-1, 1, Conv, [256, 1, 1]],  

68 [-2, 1, Conv, [256, 1, 1]],  

69 [-1, 1, Conv, [256, 3, 1]],  

70 [-1, 1, Conv, [256, 3, 1]],  

71 [-1, 1, Conv, [256, 3, 1]],  

72 [-1, 1, Conv, [256, 3, 1]],  

73 [[[-1, -3, -5, -6], 1, Concat, [1]],  

74 [-1, 1, Conv, [1024, 1, 1]], # 50  

75 ]  

76  

77 # yolov7 head  

78 head:  

79   [[-1, 1, SPPCSPC, [512]], # 51  

80  

81   [-1, 1, Conv, [256, 1, 1]],  

82   [-1, 1, nn.Upsample, [None, 2, 'nearest']],  

83   [37, 1, Conv, [256, 1, 1]], # route backbone P4  

84   [[[-1, -2], 1, Concat, [1]],  

85  

86   [-1, 1, Conv, [256, 1, 1]],  

87   [-2, 1, Conv, [256, 1, 1]],  

88   [-1, 1, Conv, [128, 3, 1]],  

89   [-1, 1, Conv, [128, 3, 1]],  

90   [-1, 1, Conv, [128, 3, 1]],  

91   [-1, 1, Conv, [128, 3, 1]],  

92   [[[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],  

93   [-1, 1, Conv, [256, 1, 1]], # 63  

94  

95   [-1, 1, Conv, [128, 1, 1]],  

96   [-1, 1, nn.Upsample, [None, 2, 'nearest']],  

97   [24, 1, Conv, [128, 1, 1]], # route backbone P3  

98   [[[-1, -2], 1, Concat, [1]],  

99  

100  [-1, 1, Conv, [128, 1, 1]],  

101  [-2, 1, Conv, [128, 1, 1]],  

102  [-1, 1, Conv, [64, 3, 1]],  

103  [-1, 1, Conv, [64, 3, 1]],  

104  [-1, 1, Conv, [64, 3, 1]],  

105  [-1, 1, Conv, [64, 3, 1]],  

106  [[[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
```

```

107 [-1, 1, Conv, [128, 1, 1]], # 75
108 ##### RECALCULATE INDEX FROM HERE #####
109 [-1, 1, Conv, [64, 1, 1]],
110 [-1, 1, nn.Upsample, [None, 2, 'nearest']],
111 [11, 1, Conv, [64, 1, 1]], # route backbone P2
112 [[-1, -2], 1, Concat, [1]], # 79
113
114
115 [-1, 1, Conv, [64, 1, 1]],
116 [-2, 1, Conv, [64, 1, 1]],
117 [-1, 1, Conv, [32, 3, 1]],
118 [-1, 1, Conv, [32, 3, 1]],
119 [-1, 1, Conv, [32, 3, 1]],
120 [-1, 1, Conv, [32, 3, 1]],
121 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
122 [-1, 1, Conv, [64, 1, 1]], # 87 HEAD 1
123
124
125 [-1, 1, MP, []],
126 [-1, 1, Conv, [64, 1, 1]],
127 [-3, 1, Conv, [64, 1, 1]],
128 [-1, 1, Conv, [64, 3, 2]],
129 [[-1, -3, 75], 1, Concat, [1]], # 92
130
131
132 [-1, 1, Conv, [128, 1, 1]],
133 [-2, 1, Conv, [128, 1, 1]],
134 [-1, 1, Conv, [64, 3, 1]],
135 [-1, 1, Conv, [64, 3, 1]],
136 [-1, 1, Conv, [64, 3, 1]],
137 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
138 [-1, 1, Conv, [128, 1, 1]], # 100 HEAD 2
139
140
141
142 [-1, 1, MP, []],
143 [-1, 1, Conv, [128, 1, 1]],
144 [-3, 1, Conv, [128, 1, 1]],
145 [-1, 1, Conv, [128, 3, 2]],
146 [[-1, -3, 63], 1, Concat, [1]], #105
147
148
149 [-1, 1, Conv, [256, 1, 1]],
150 [-2, 1, Conv, [256, 1, 1]],
151 [-1, 1, Conv, [128, 3, 1]],
152 [-1, 1, Conv, [128, 3, 1]],
153 [-1, 1, Conv, [128, 3, 1]],
154 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
155 [-1, 1, Conv, [256, 1, 1]], # 113 HEAD 3
156
157
158 [-1, 1, MP, []],
159 [-1, 1, Conv, [256, 1, 1]],
160 [-3, 1, Conv, [256, 1, 1]],
161 [-1, 1, Conv, [256, 3, 2]],
162 [[-1, -3, 51], 1, Concat, [1]], # 118
163 [-1, 1, Conv, [512, 1, 1]],

```

```

164 [-1, 1, Conv, [256, 3, 1]],  

165 [-1, 1, Conv, [256, 3, 1]],  

166 [-1, 1, Conv, [256, 3, 1]],  

167 [-1, 1, Conv, [256, 3, 1]],  

168 [[[-1, -2, -3, -4, -5, -6], 1, Concat, [1]]],  

169 [-1, 1, Conv, [512, 1, 1]], # 126 HEAD 4  

170  

171 #[75, 1, RepConv, [256, 3, 1]],  

172 #[88, 1, RepConv, [512, 3, 1]],  

173 #[101, 1, RepConv, [1024, 3, 1]],  

174  

175 [87, 1, RepConv, [128, 3, 1]], # 127  

176 [100, 1, RepConv, [256, 3, 1]],  

177 [113, 1, RepConv, [512, 3, 1]],  

178 [126, 1, RepConv, [1024, 3, 1]],  

179  

180  

181 [[127, 128, 129, 130], 1, IDetect, [nc, anchors]], # Detect(P3, P4, P5)  

182 ]

```

YOLOv7 + rerouting Architecture Configuration

```

1 # parameters  

2 nc: 4 # number of classes  

3 depth_multiple: 1.0 # model depth multiple  

4 width_multiple: 1.0 # layer channel multiple  

5  

6 # anchors  

7 anchors:  

8   #- [12,16, 19,36, 40,28] # P3/8  

9   #- [36,75, 76,55, 72,146] # P4/16  

10  #- [142,110, 192,243, 459,401] # P5/32  

11  - [4,4, 14,5, 11,11] # P3/8  

12  - [27,8, 18,17, 41,14] # P4/16  

13  - [43,32, 86,27, 149,70] # P5/32  

14  

15 # yolov7 backbone  

16 backbone:  

17   # [from, number, module, args]  

18   [[-1, 1, Conv, [32, 3, 1]], # 0  

19  

20   [-1, 1, Conv, [64, 3, 2]], # 1-P1/2  

21   [-1, 1, Conv, [64, 3, 1]],  

22  

23   [-1, 1, Conv, [128, 3, 2]], # 3-P2/4  

24   [-1, 1, Conv, [64, 1, 1]],  

25   [-2, 1, Conv, [64, 1, 1]],  

26   [-1, 1, Conv, [64, 3, 1]],  

27   [-1, 1, Conv, [64, 3, 1]],  

28   [-1, 1, Conv, [64, 3, 1]],  

29   [-1, 1, Conv, [64, 3, 1]],  

30   [[-1, -3, -5, -6], 1, Concat, [1]],  

31   [-1, 1, Conv, [256, 1, 1]], # 11  

32  

33   [-1, 1, MP, []],  

34   [-1, 1, Conv, [128, 1, 1]],  


```

```

35     [-3, 1, Conv, [128, 1, 1]],
36     [-1, 1, Conv, [128, 3, 2]],
37     [[[-1, -3], 1, Concat, [1]], # 16-P3/8
38     [-1, 1, Conv, [128, 1, 1]],
39     [-2, 1, Conv, [128, 1, 1]],
40     [-1, 1, Conv, [128, 3, 1]],
41     [-1, 1, Conv, [128, 3, 1]],
42     [-1, 1, Conv, [128, 3, 1]],
43     [-1, 1, Conv, [128, 3, 1]],
44     [[[-1, -3, -5, -6], 1, Concat, [1]],
45     [-1, 1, Conv, [512, 1, 1]], # 24
46
47     [-1, 1, MP, []],
48     [-1, 1, Conv, [256, 1, 1]],
49     [-3, 1, Conv, [256, 1, 1]],
50     [-1, 1, Conv, [256, 3, 2]],
51     [[[-1, -3], 1, Concat, [1]], # 29-P4/16
52     [-1, 1, Conv, [256, 1, 1]],
53     [-2, 1, Conv, [256, 1, 1]],
54     [-1, 1, Conv, [256, 3, 1]],
55     [-1, 1, Conv, [256, 3, 1]],
56     [-1, 1, Conv, [256, 3, 1]],
57     [-1, 1, Conv, [256, 3, 1]],
58     [[[-1, -3, -5, -6], 1, Concat, [1]],
59     [-1, 1, Conv, [1024, 1, 1]], # 37
60
61     [-1, 1, MP, []],
62     [-1, 1, Conv, [512, 1, 1]],
63     [-3, 1, Conv, [512, 1, 1]],
64     [-1, 1, Conv, [512, 3, 2]],
65     [[[-1, -3], 1, Concat, [1]], # 42-P5/32
66     [-1, 1, Conv, [256, 1, 1]],
67     [-2, 1, Conv, [256, 1, 1]],
68     [-1, 1, Conv, [256, 3, 1]],
69     [-1, 1, Conv, [256, 3, 1]],
70     [-1, 1, Conv, [256, 3, 1]],
71     [-1, 1, Conv, [256, 3, 1]],
72     [[[-1, -3, -5, -6], 1, Concat, [1]],
73     [-1, 1, Conv, [1024, 1, 1]], # 50
74 ]
75
76 # yolov7 head
77 head:
78     [[-1, 1, SPPCSPC, [512]], # 51
79
80     [-1, 1, Conv, [256, 1, 1]],
81     [-1, 1, nn.Upsample, [None, 2, 'nearest']],
82     [37, 1, Conv, [256, 1, 1]], # route backbone P4
83     [[-1, -2], 1, Concat, [1]],
84
85     [-1, 1, Conv, [256, 1, 1]],
86     [-2, 1, Conv, [256, 1, 1]],
87     [-1, 1, Conv, [128, 3, 1]],
88     [-1, 1, Conv, [128, 3, 1]],
89     [-1, 1, Conv, [128, 3, 1]],
90     [-1, 1, Conv, [128, 3, 1]],
91     [[[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],

```

```

92 [-1, 1, Conv, [256, 1, 1]], # 63
93
94 [-1, 1, Conv, [128, 1, 1]],
95 [-1, 1, nn.Upsample, [None, 4, 'nearest']],
96 [11, 1, Conv, [128, 1, 1]], # route backbone P3
97 [[-1, -2], 1, Concat, [1]],
98
99 [-1, 1, Conv, [128, 1, 1]],
100 [-2, 1, Conv, [128, 1, 1]],
101 [-1, 1, Conv, [64, 3, 1]],
102 [-1, 1, Conv, [64, 3, 1]],
103 [-1, 1, Conv, [64, 3, 1]],
104 [-1, 1, Conv, [64, 3, 1]],
105 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
106 [-1, 1, Conv, [128, 1, 1]], # 75
107
108 # RECALCULATE FROM HERE
109 # downsample after use in 75
110 [-1, 1, MP, []],
111 [-1, 1, Conv, [128, 1, 2]],
112 [-3, 1, Conv, [128, 1, 1]],
113 [-1, 1, Conv, [128, 3, 4]],
114 [[-1, -3, 63], 1, Concat, [1]], # 80
115
116 [-1, 1, Conv, [256, 1, 1]],
117 [-2, 1, Conv, [256, 1, 1]],
118 [-1, 1, Conv, [128, 3, 1]],
119 [-1, 1, Conv, [128, 3, 1]],
120 [-1, 1, Conv, [128, 3, 1]],
121 [-1, 1, Conv, [128, 3, 1]],
122 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
123 [-1, 1, Conv, [256, 1, 1]], # 88
124
125 [-1, 1, MP, []],
126 [-1, 1, Conv, [256, 1, 1]],
127 [-3, 1, Conv, [256, 1, 1]],
128 [-1, 1, Conv, [256, 3, 2]],
129 [[-1, -3, 51], 1, Concat, [1]],
130
131 [-1, 1, Conv, [512, 1, 1]],
132 [-2, 1, Conv, [512, 1, 1]],
133 [-1, 1, Conv, [256, 3, 1]],
134 [-1, 1, Conv, [256, 3, 1]],
135 [-1, 1, Conv, [256, 3, 1]],
136 [-1, 1, Conv, [256, 3, 1]],
137 [[-1, -2, -3, -4, -5, -6], 1, Concat, [1]],
138 [-1, 1, Conv, [512, 1, 1]], # 101
139
140 [75, 1, RepConv, [256, 3, 1]],
141 [88, 1, RepConv, [512, 3, 1]],
142 [101, 1, RepConv, [1024, 3, 1]],
143
144 [[102, 103, 104], 1, IDetect, [nc, anchors]], # Detect(P3, P4, P5)
145 ]

```

APPENDIX B

Compute EIoU

```
1 def bbox_iou(box1, box2, x1y1x2y2=True, eps=1e-7):
2     # Returns the IoU of box1 to box2. box1 is 4, box2 is nx4
3     box2 = box2.T
4
5     # Get the coordinates of bounding boxes
6     if x1y1x2y2: # x1, y1, x2, y2 = box1
7         b1_x1, b1_y1, b1_x2, b1_y2 = box1[0], box1[1], box1[2], box1[3]
8         b2_x1, b2_y1, b2_x2, b2_y2 = box2[0], box2[1], box2[2], box2[3]
9     else: # transform from xywh to xyxy
10        b1_x1, b1_x2 = box1[0] - box1[2] / 2, box1[0] + box1[2] / 2
11        b1_y1, b1_y2 = box1[1] - box1[3] / 2, box1[1] + box1[3] / 2
12        b2_x1, b2_x2 = box2[0] - box2[2] / 2, box2[0] + box2[2] / 2
13        b2_y1, b2_y2 = box2[1] - box2[3] / 2, box2[1] + box2[3] / 2
14
15
16    w1, h1 = b1_x2 - b1_x1, b1_y2 - b1_y1 + eps
17    w2, h2 = b2_x2 - b2_x1, b2_y2 - b2_y1 + eps
18
19    x0 = torch.min(b1_x1, b2_x1) # topleftest of top left of the boxes
20    y0 = torch.min(b1_y1, b2_y1)
21    x1 = torch.max(b1_x1, b2_x1) # bottomrightest of toplefts
22    y1 = torch.max(b1_y1, b2_y1)
23    x2 = torch.min(b1_x2, b2_x2) # topleftest of bottomrights
24    y2 = torch.min(b1_y2, b2_y2)
25
26    xmin = torch.min(x1, x2)
27    ymin = torch.min(y1, y2)
28    xmax = torch.max(x1, x2)
29    ymax = torch.max(y1, y2)
30
31    inter = (x2-x0)*(y2-y0) + \
32            (xmin-x0)*(ymin-y0) - \
33            (x1-x0)*(ymax-y0) - \
34            (xmax-x0)*(y1-y0)
35
36    union = w1 * h1 + w2 * h2 - inter + eps
37    return inter/union # using this just for covexication
38    #return torch.min(inter/union, torch.Tensor([1.0]).cuda()) # use this ←
39    # return for EIoU without covexication
```

EIoU Loss

```
1 class ComputeLossOTA_EIoU(ComputeLossOTA):
2     def __call__(self, p, targets, imgs): # predictions, targets, model
3         device = targets.device
4         lcls, lbox, lobj = torch.zeros(1, device=device), torch.zeros(1, ←
5             device=device), torch.zeros(1, device=device)
```

```

5     bs, as_, gjs, gis, targets, anchors = self.build_targets(p, ←
6         targets, imgs)
7     pre_gen_gains = [torch.tensor(pp.shape, device=device)[[3, 2, 3, ←
8         2]] for pp in p]
9
10
11    # Losses
12    for i, pi in enumerate(p): # layer index, layer predictions
13        b, a, gj, gi = bs[i], as_[i], gjs[i], gis[i] # image, anchor←
14            , gridy, gridx
15        tobj = torch.zeros_like(pi[..., 0], device=device) # target ←
16            obj
17
18        n = b.shape[0] # number of targets
19        if n:
20            ps = pi[b, a, gj, gi] # prediction subset corresponding ←
21                to targets
22
23            # Regression
24            grid = torch.stack([gi, gj], dim=1)
25            pxy = ps[:, :2].sigmoid() * 2. - 0.5
26            #pxy = ps[:, :2].sigmoid() * 3. - 1.
27            pwh = (ps[:, 2:4].sigmoid() * 2) ** 2 * anchors[i]
28            bbox = torch.cat((pxy, pwh), 1) # predicted box
29            selected_tbox = targets[i][:, 2:6] * pre_gen_gains[i]
30            selected_tbox[:, :2] -= grid
31            iou = bbox_iou(bbox.T, selected_tbox, x1y1x2y2=False, ←
32                EIoU=True) # iou(prediction, target)
33            lbox += ((1.0 - iou)**2).mean() # iou loss # using ←
34                square for covexication
35
36    # Objectness
37    tobj[b, a, gj, gi] = (1.0 - self.gr) + self.gr * iou.←
38        detach().clamp(0).type(tobj.dtype) # iou ratio
39
40    # Classification
41    selected_tcls = targets[i][:, 1].long()
42    if self.nc > 1: # cls loss (only if multiple classes)
43        t = torch.full_like(ps[:, 5:], self.cn, device=device.←
44            ) # targets
45        t[range(n), selected_tcls] = self.cp
46        lcls += self.BCEcls(ps[:, 5:], t) # BCE
47
48    # Append targets to text file
49    # with open('targets.txt', 'a') as file:
50    #     [file.write('%11.5g ' * 4 % tuple(x) + '\n') for x ←
51     in torch.cat((txy[i], twh[i]), 1)]
52
53    obji = self.BCEobj(pi[..., 4], tobj)
54    lobj += obji * self.balance[i] # obj loss
55    if self.autobalance:
56        self.balance[i] = self.balance[i] * 0.9999 + 0.0001 / ←
57            obji.detach().item()
58
59    if self.autobalance:
60        self.balance = [x / self.balance[self.ssi] for x in self.←
61            balance]

```

```

50     lbox *= self.hyp['box']
51     lobj *= self.hyp['obj']
52     lcls *= self.hyp['cls']
53     bs = tobj.shape[0] # batch size
54
55     loss = lbox + lobj + lcls
56     return loss * bs, torch.cat((lbox, lobj, lcls, loss)).detach()

```

Anchor-free Loss Numerical Stabilization

```

1  class ComputeLossStabilized(ComputeLoss):
2      def __call__(self, p, targets, img=None, epoch=0):
3          loss = torch.zeros(3, device=self.device) # box, cls, dfl
4          feats, pred_distri, pred_scores = p
5          pred_scores = pred_scores.permute(0, 2, 1).contiguous()
6          pred_distri = pred_distri.permute(0, 2, 1).contiguous()
7
8          dtype = pred_scores.dtype
9          batch_size, grid_size = pred_scores.shape[:2]
10         imgs = torch.tensor(feats[0].shape[2:], device=self.device, ←
11             dtype=dtype) * self.stride[0] # image size (h,w)
12         anchor_points, stride_tensor = make_anchors(feats, self.stride, ←
13             0.5)
14
15         # targets
16         targets = self.preprocess(targets, batch_size, scale_tensor=imgs←
17             [[1, 0, 1, 0]])
18         gt_labels, gt_bboxes = targets.split((1, 4), 2) # cls, xyxy
19         mask_gt = gt_bboxes.sum(2, keepdim=True).gt_(0)
20
21         # pboxes
22         pred_bboxes = self.bbox_decode(anchor_points, pred_distri) # ←
23             xyxy, (b, h*w, 4)
24
25         target_labels, target_bboxes, target_scores, fg_mask = self.←
26             assigner(
27                 pred_scores.detach().sigmoid(),
28                 (pred_bboxes.detach() * stride_tensor).type(gt_bboxes.dtype),
29                 anchor_points * stride_tensor,
30                 gt_labels,
31                 gt_bboxes,
32                 mask_gt)
33
34         target_bboxes /= stride_tensor
35         target_scores_sum = target_scores.sum()
36         target_scores_sum = max(1, target_scores_sum) # numerical ←
37             stabilization
38
39         # cls loss
40         # loss[1] = self.varifocal_loss(pred_scores, target_scores, ←
41             target_labels) / target_scores_sum # VFL way
42         loss[1] = self.BCEcls(pred_scores, target_scores.to(dtype)).sum()←
43             / (target_scores_sum) # BCE
44
45         # bbox loss
46         if fg_mask.sum():
47             loss[0], loss[2], iou = self.bbox_loss(pred_distri,

```

```
39                                         pred_bboxes,
40                                         anchor_points,
41                                         target_bboxes,
42                                         target_scores,
43                                         target_scores_sum,
44                                         fg_mask)
45
46     loss[0] *= 7.5 # box gain
47     loss[1] *= 0.5 # cls gain
48     loss[2] *= 1.5 # dfl gain
49
50     return loss.sum() * batch_size, loss.detach() # loss(box, cls, ←
      dfl)
```

APPENDIX C

Request for Permission to Reproduce Figure in a Final Project Report

DS Dion Andreas Solang
To: liao@iis.sinica.edu.tw

Fri 30/06/2023 08:00

Dear Dr. Liao,

I hope this email finds you well. My name is Dion Andreas Solang, and I am an undergraduate student at Institut Teknologi Sepuluh Nopember, Indonesia. I am writing to request for permission to include figures from your work in "YOLOv7: Trainable bag-of-freebies sets new state-of-the-art for real-time object detectors" and "Designing Network Design Strategies Through Gradient Path Analysis", in a final project report I am preparing for my course.

The figures I'm referring to are Fig. 1 and Fig. 5 of the YOLOv7 paper and Fig. 6 of the ELAN paper. I assure you that proper citation and acknowledgement will be given to your work, as per standard academic practice. I will include a caption beneath the figures indicating the source of the figures as well as the necessary citation information, ensuring that your work is appropriately credited.

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Sincerely,

Dion

廖弘源 <liao@iis.sinica.edu.tw>
To: Dion Andreas Solang
Cc: kinyiu <kinyiu@iis.sinica.edu.tw>; liao <liao@iis.sinica.edu.tw>

Fri 30/06/2023 14:07

Dion,

Ok. No problem.

Best,
Mark

...

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Request for Permission to Reproduce Figure in a Final Project Report

DS Dion Andreas Solang
To: fabio.cuzzolin@brookes.ac.uk

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Dear Professor Cuzzolin,

I hope this email finds you well. My name is Dion Andreas Solang, and I am an undergraduate student at Institut Teknologi Sepuluh Nopember, Indonesia. I am writing to request for permission to include figures from your work in "YOLO-Z: Improving small object detection in YOLOv5 for autonomous vehicles" in a final project report I am preparing for my course.

The figures I'm referring to are Fig. 7 and Fig. 8 of the YOLO-Z paper. I assure you that proper citation and acknowledgement will be given to your work, as per standard academic practice. I will include a caption beneath the figures indicating the source of the figures as well as the necessary citation information, ensuring that your work is appropriately credited.

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Sincerely,

Dion

FC Fabio Cuzzolin <fabio.cuzzolin@brookes.ac.uk>
To: Dion Andreas Solang

Fri 30/06/2023 15:52

Dear Dion,

absolutely no problem, and thanks for your interest in our work!

Fabio

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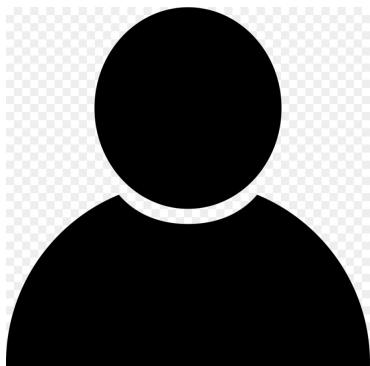
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AUTHOR'S BIOGRAPHY



Dion Andreas Solang, born on the day he was born, was a creature with many interests. He began his journey on exploring computer science and engineering when he was in his third year of middle school. He encountered a random C programming language book in a bookstore, bought it, read it, and created his first hello world right after.

His training arc started in high school. Due to an unknown reason, his homeroom teacher forced him to enroll in the high school's mathematics olympiad team. As he was a pushover back then, he just followed what his teacher said. Fortunately, the math teacher didn't really want to teach olympiad level math, and recommended him to try informatics olympiad instead. That's how he met his master who taught him the competitive programming 101 and robotics.

Fast-forward to his university year, he enrolled in an autonomous surface vehicle student team. There, he learned the art of multidisciplinary teamwork and a lot of failure analysis technique. He was once tasked on developing a computer vision system for a robot. This final project was actually a continuation from that system.

Most of his activities during the making of this final project includes listening Trash Taste podcast, playing saxophone, and watching v-tubers. Honestly, most of the work here is done by the red computer in B201 lab. With model training lasts around a day for each model, he can't help but spend those idle time to things other than this final project. Therefore, let's just forget about Dion Andreas Solang because that red computer is the real hero for this one.

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