

Master-Praktikum - Learning for self-driving cars and intelligent systems - Winter 2019/20

Weekly Report : Sensor Modality Fusion

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Accomplished tasks:

- Successfully run some networks that only use lidar input to perform 3d detection
 - VoxelNet: because the training takes so long, we train only a few epochs
 - PointRCNN: use pre-trained weights to predict in test set. Training still needs some debugging
- Successfully run some networks that only use monocular image to perform 3d detection
- Successfully run a fusion network: PointFusion
- Visualize the prediction result of above mentioned networks

Tasks planned for next week:

- Tune PointFusion's structure
- Split the training set into training, evaluation and test set

Issues / Roadblocks:

- Because the test set of KITTI dataset does not have labels, we can only visualize the prediction result to evaluate.