

Weekly Progress Report

Oct 4 - 8th, 2021

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Noah's Ark | Autonomous Driving Lab
LiDAR Domain Adaptation

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Weekly Summary

- Done:

- Checking for once_eval_metric
- Writing script for evaluation
 - Picking the best checkpoint in terms of
 - Average mAP for BEV of the 4 classes {car, truck, pedestrian, cyclist}
 - Threshold = 0.3, 0.5, 0.7 ?
- Plot best checkpoint for each evaluation (oracle)
 - Oracle:
 - p40 \rightarrow p40
 - ONCE \rightarrow ONCE
 - M2 \rightarrow M2

- In Progress:

- Plot best checkpoint for each evaluation (naive)
 - Naive:
 - ONCE \rightarrow M2
 - p40 \rightarrow M2

- Recent Goals:

- Understanding: once_metric vs kitti metric
- Visualize frames having good and bad performances

Work Logs

- Oct 4 (Monday)
 - Re-evaluate once dataset (was not evaluated using kitti metrics)
 - Has “eval_metric: kitti” but not outputting the kitti output
 - Result: we cannot use KITTI metric for ONCE due to its lack of information
 - Writing script for evaluation
 - Picking the best checkpoint in terms of
 - Average mAP for BEV of the 4 classes {car, truck, pedestrian, cyclist)
 - Threshold = 0.3, 0.5, 0.7

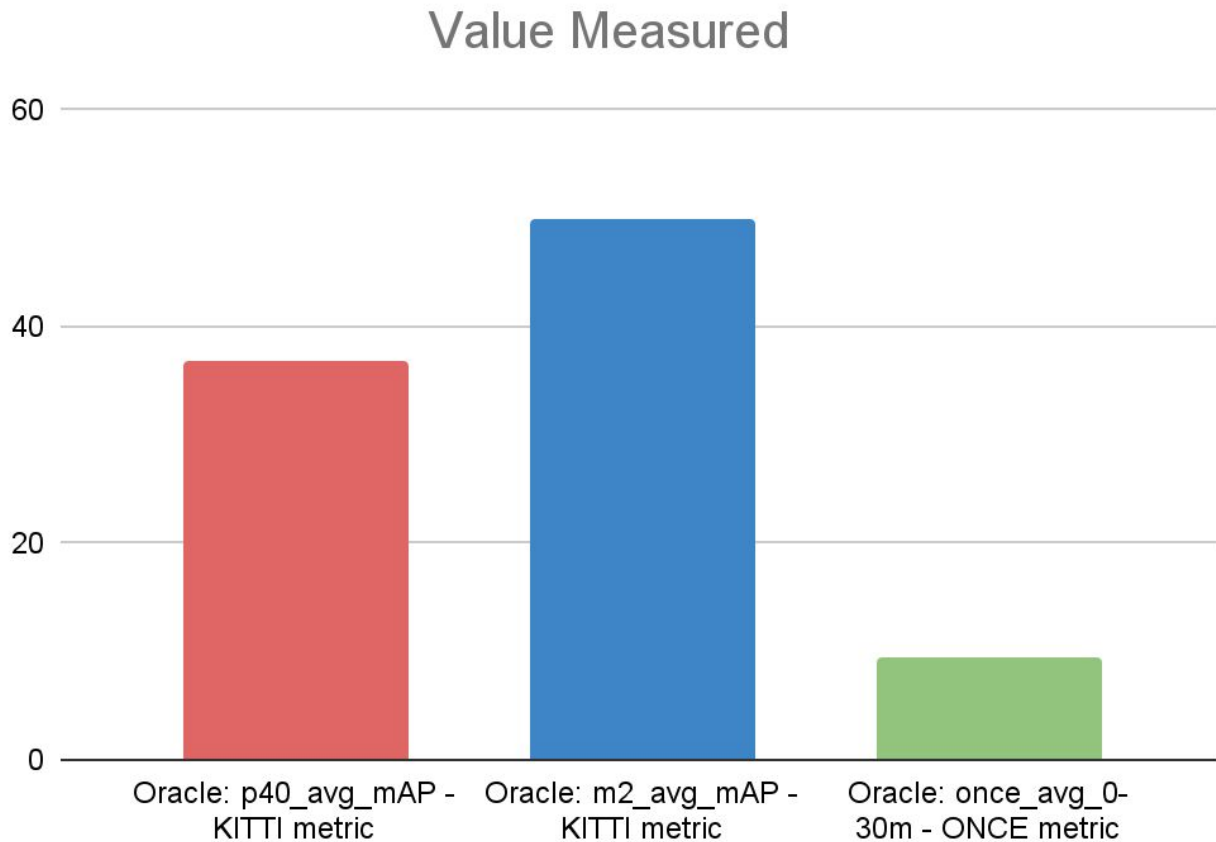
Work Logs

- Oct 5 (Tuesday)
 - Developed “evel_log_extraction.py”
 - p40: oracle

	Measured value	ckp#
Oracle: p40_avg_mAP - KITTI metric	36.81543	74
Oracle: m2_avg_mAP - KITTI metric	50.03165	58
Oracle: once_avg_0-30m - ONCE metric	9.5	74

Work Logs

➡ - Oct 5 (Tuesday) (cont')



End of October 8th, Weekly Report