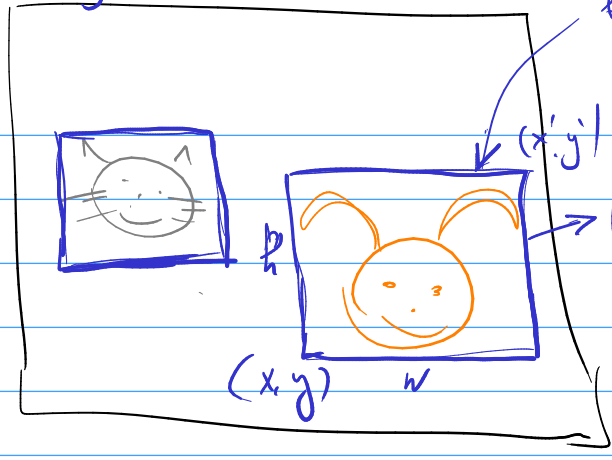


Object localization



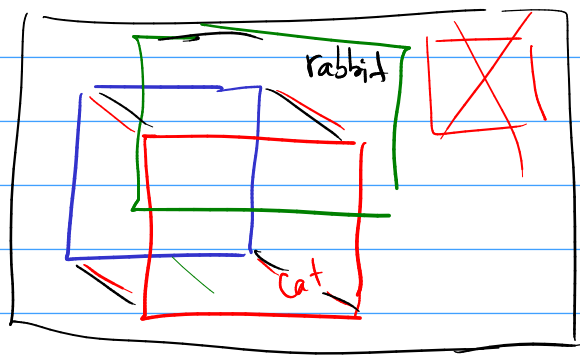
Object detection



bounding box
bbox

$$(p, \bar{c}, x, y, w, h)$$

↑
confidence



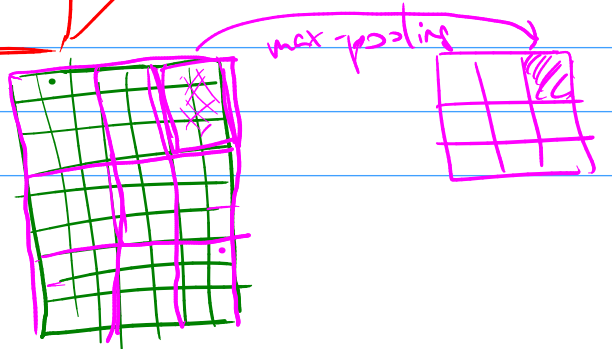
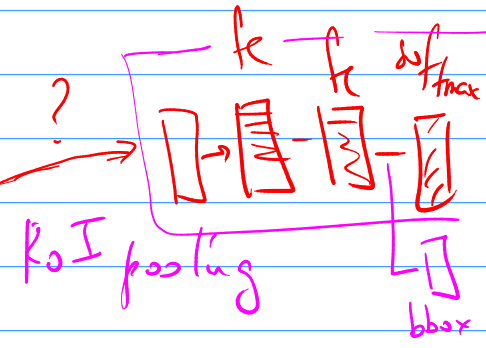
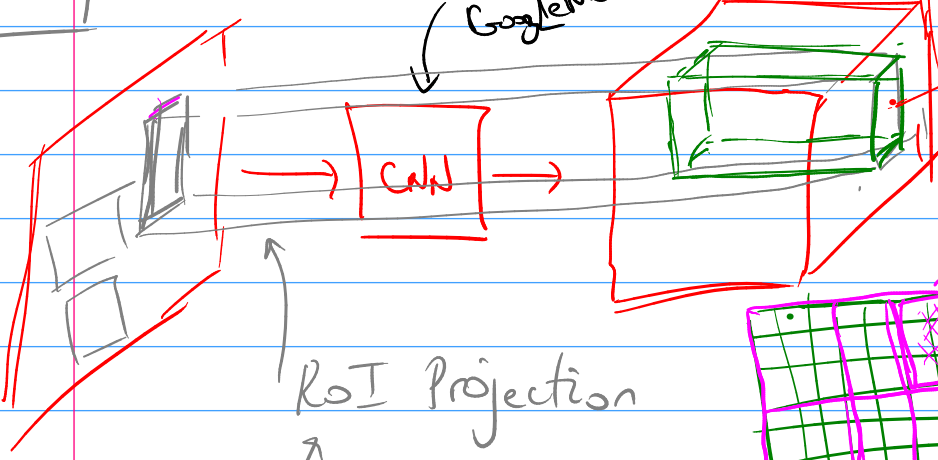
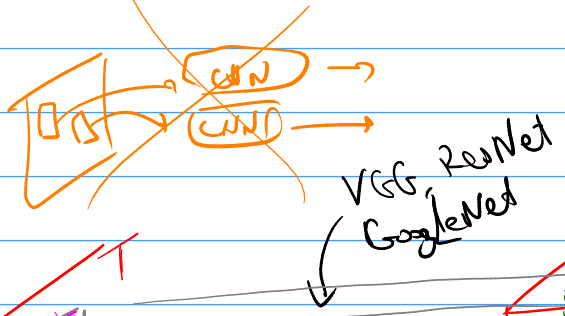
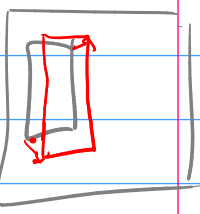
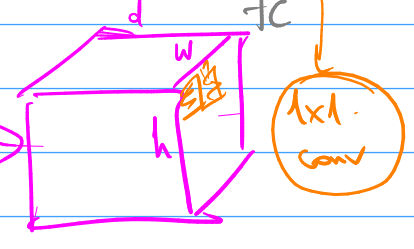
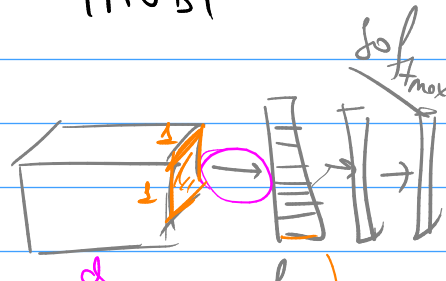
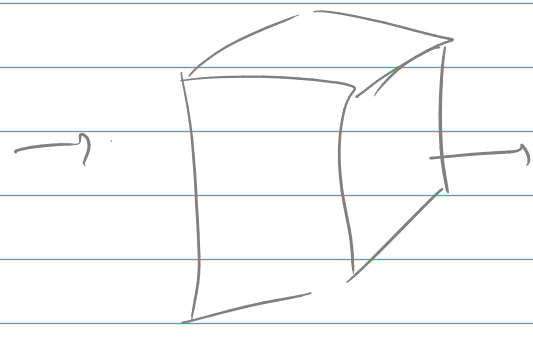
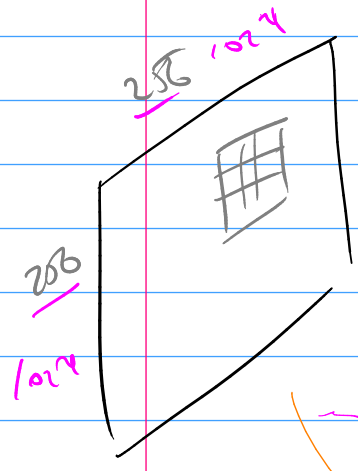
$$(p, \bar{c}, x, y, w, h)$$

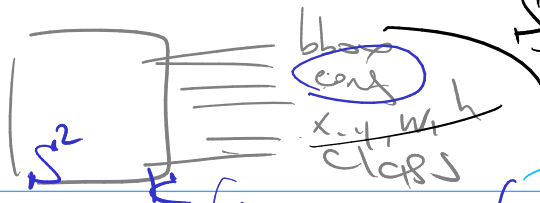
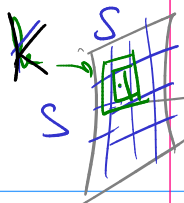
↓ ↓ ↓ ↓ ↓ ↓

$$(\bar{c}, x, y, w, h)$$

$$J_{iou} = \frac{|A \cap B|}{|A \cup B|}$$

Jaccard

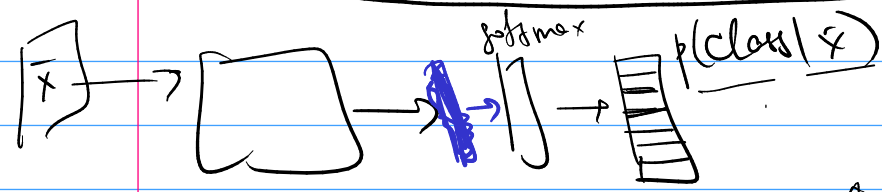




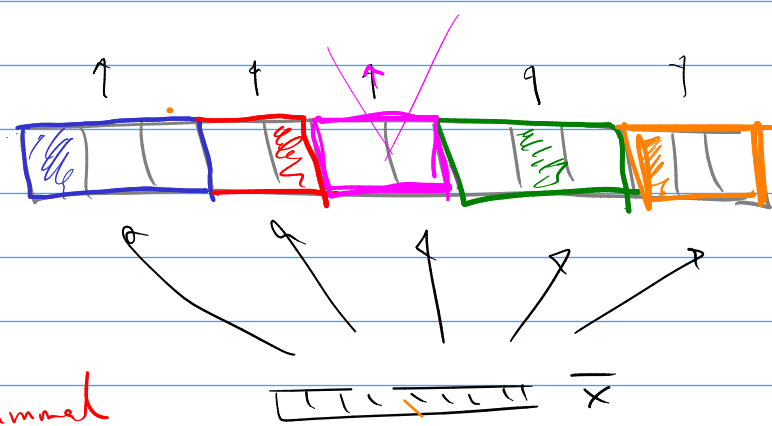
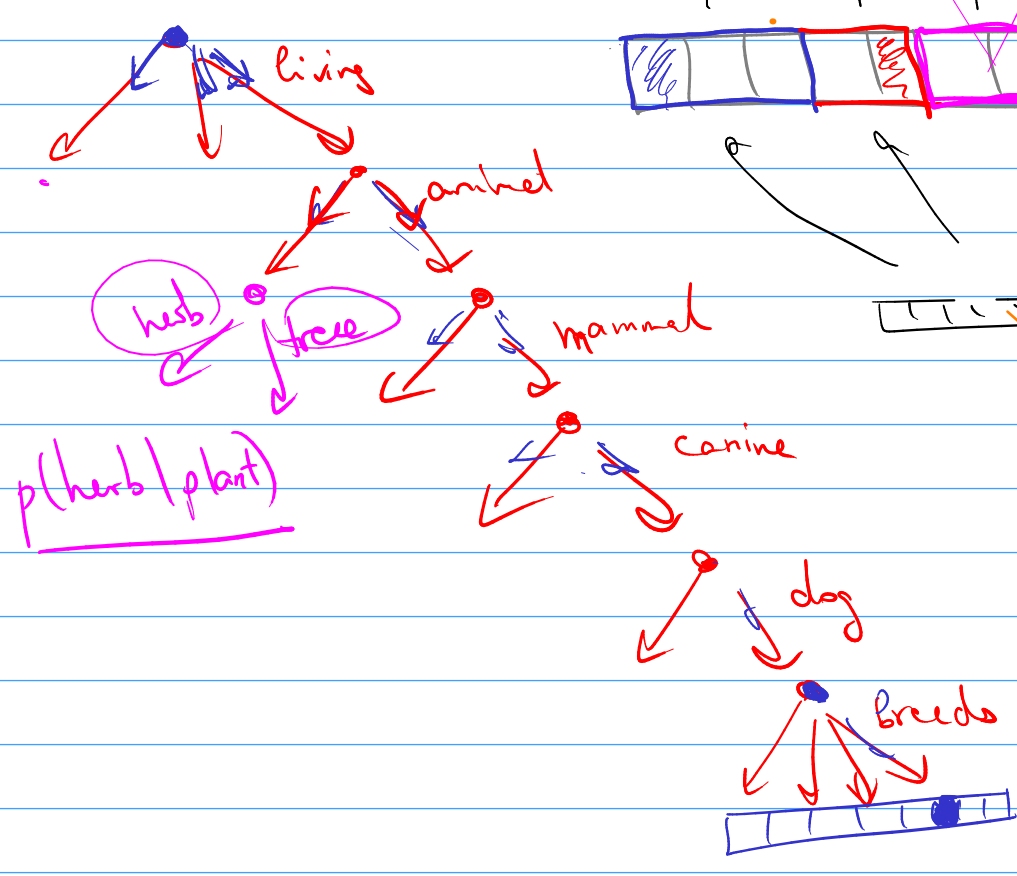
$$S \times S \times (C + 5K)$$

reorganized
block

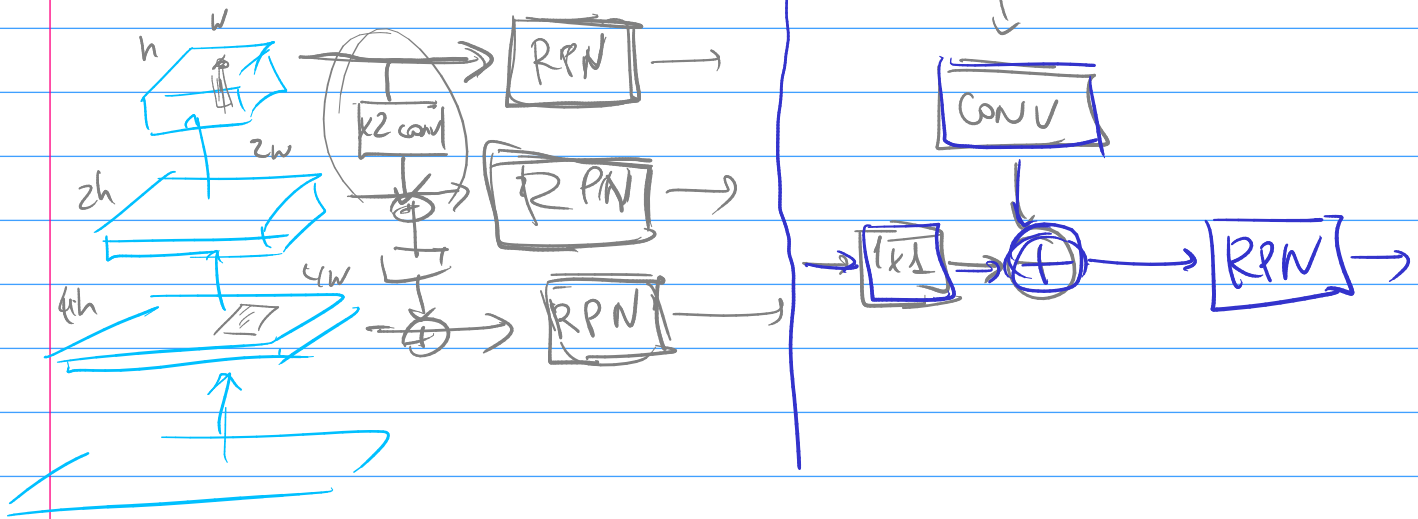
$$L = \sum_{S=1}^K \sum_{k=1}^K \left(\lambda_1 [npch_block] \cdot \left((\hat{x} - x)^2 + (\hat{y} - y)^2 + (\hat{w} - w)^2 + (\hat{h} - h)^2 \right) + \lambda_2 [npch_block] \cdot L_{class}(\hat{c}, c) + \lambda_3 [npch_block] \cdot (p - 1)^2 + \lambda_4 [npch_block] \cdot (q - 0)^2 \right)$$



Hierarchical softmax



Feature Pyramid Networks



p - вероятность
 $y = 1$, да
 $= 0$, нет

$$L(p, y) = -y \log p - (1-y) \log(1-p)$$

$p = 0.8, y = 1 \rightarrow L = -\log \frac{4}{5} = 0.32$

$p = 0.2, y = 1 \rightarrow L = -\log \frac{1}{5} = 2.32$

10^5
 10