

Special Issue

Object Detection via Point Cloud Data

Message from the Guest Editors

Autonomous platforms often require the ability to interact with objects in their immediate environment. These interactions can manifest, for example, as simple pick-and-place operations or as complex coordinations between multiple robotic agents. Nonetheless, at either end of the complexity scale, the decision-making requires to perform interactions requires an a priori level of situational awareness. Situational awareness encapsulates the ability to perceive, understand and predict elements within a given environment to make informed decisions. A key belief required to facilitate object interactions is to first detect the object. Detection, in this sense, amounts to determining (i) where an object is and (ii) what an object is. This detection takes place at the perception and comprehension stages of situational awareness and is often facilitated via the interpretation of dense 3D point cloud measurements. This Special Issue requests papers that address problems related to object detection via point cloud data, as well as the limitations of existing approaches.

Guest Editors

Prof. Dr. Peter Ross McAree

School of Mechanical and Mining Engineering, Faculty of Engineering, Architecture and Information Technology, The University of Queensland, St Lucia, QLD 4072, Australia

Dr. Tyson Phillips

School of Mechanical and Mining Engineering, Faculty of Engineering, Architecture and Information Technology, The University of Queensland, Brisbane St Lucia, QLD 4072, Australia

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Sensors
Editorial Office
MDPI, Grosspeteranlage 5
4052 Basel, Switzerland
Tel: +41 61 683 77 34
sensors@mdpi.com

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Editor-in-Chief

Prof. Dr. Vittorio M. N. Passaro
Department of Electrical and Information Engineering, Politecnico di
Bari, Via Orabona 4, 70126 Bari, Italy

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