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JULY 2017

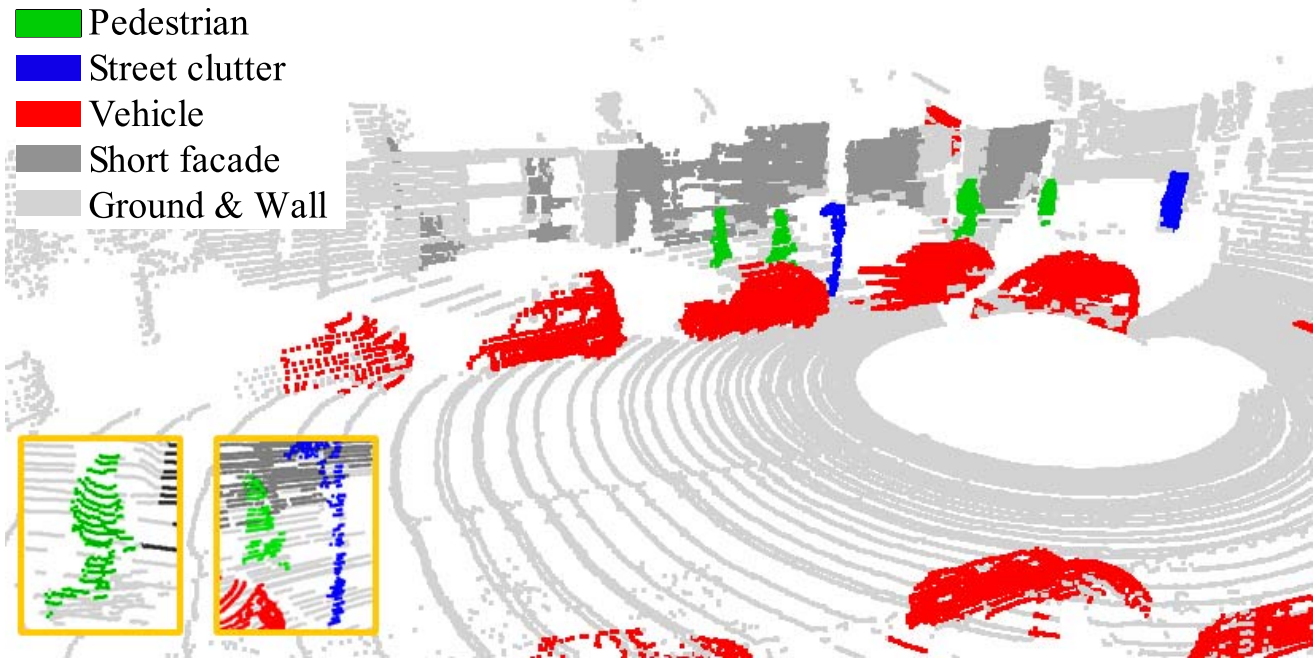
VOLUME 14

NUMBER 7

IGRSBY

(ISSN 1545-598X)

-  Pedestrian
-  Street clutter
-  Vehicle
-  Short facade
-  Ground & Wall



Object classification result on urban point cloud using deep learning and contextual analysis.

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About the Cover: Result of object classification in a point cloud frame recorded by a Velodyne HDL-64 Lidar scanner in a dense urban environment. The detection and categorization is performed in real time, based on a deep learning based object appearance model, and object context analysis ensuring valid spatial alignment relations between various scene entities. In particular, vehicles and pedestrians are distinguished from other street clutter elements and wall segments, which objects are crucial for autonomous driving control systems. For more information please see “Instant Object Detection in Lidar Point Clouds,” by Börçs *et al.*, which begins on page 992.