

ABSTRACT

Disclosed are a method and apparatus for object detection, an electronic device and a computer storage medium. The method includes: acquiring three-dimensional (3D) point cloud data; determining point cloud semantic features corresponding to the 3D point cloud data according to the 3D point cloud data; determining part location information of foreground points based on the point cloud semantic features; extracting at least one initial 3D bounding box based on the point cloud data; and determining a 3D bounding box for an object according to the point cloud semantic features corresponding to the point cloud data, the part location information of the foreground points and the at least one initial 3D bounding box. In this way, the point cloud semantic feature is directly obtained from the 3D point cloud data to determine the part location information of the foreground points, and the 3D bounding box for the object is further determined according to the point cloud semantic features, the part location information of the foreground points and the at least one 3D box. There is no need to project the 3D point cloud data to a top view and obtain a box in the top view by use of a two-dimensional (2D) detection technology, and loss of original information of a point cloud is avoided during quantification.

[Figure 1]