

# 3D Semantic Occupancy Prediction from Monocular Camera - First report

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This project involves estimating the occupancy and semantic labels of the objects in a 3D scene using sensor data monocular camera images. The occupancy refers to whether a particular voxel or region in the scene is occupied by an object or not, while the semantic labels refer to the specific object categories, such as cars, pedestrians, buildings, and trees.

Monocular camera images

**Ajouter images ? ?**

3D semantic occupancy map of the scene. The 3D occupancy map will be represented as a voxel grid, where each voxel will be labelled with a semantic class. The model also predicts the occupancy probability of each voxel in the voxel grid.

**Ajouter images ? ?**

Zotero bibliography ??

