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In LiDAR, laser light is sent from a source (transmitter) and reflected from objects in the scene.

The reflected light is detected by the system receiver and the

time of flight (TOF) is used to develop a distance map of the objects in the scene.

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[The object-wise feature extractors project LiDAR point clouds into 2D representations and generate the object proposals using 2D networks.](#)

[Then, they regress the region proposals to predict the 3D bounding boxes.](#)

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