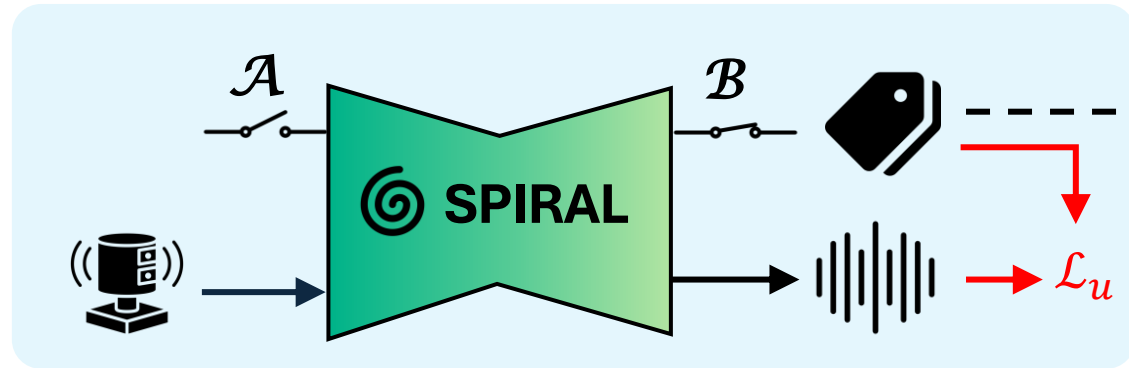
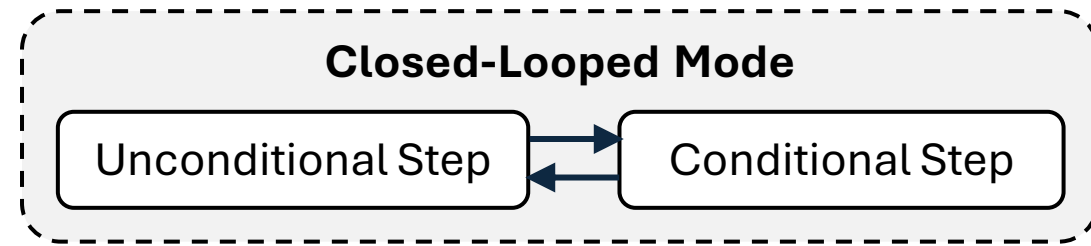
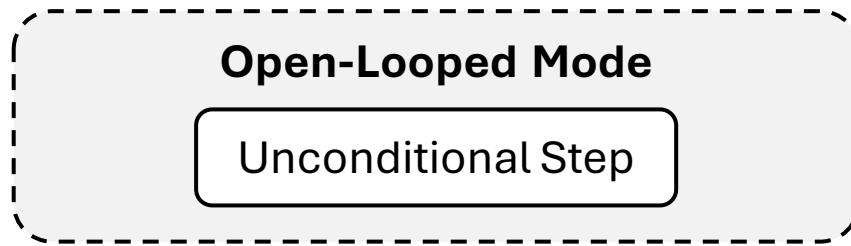
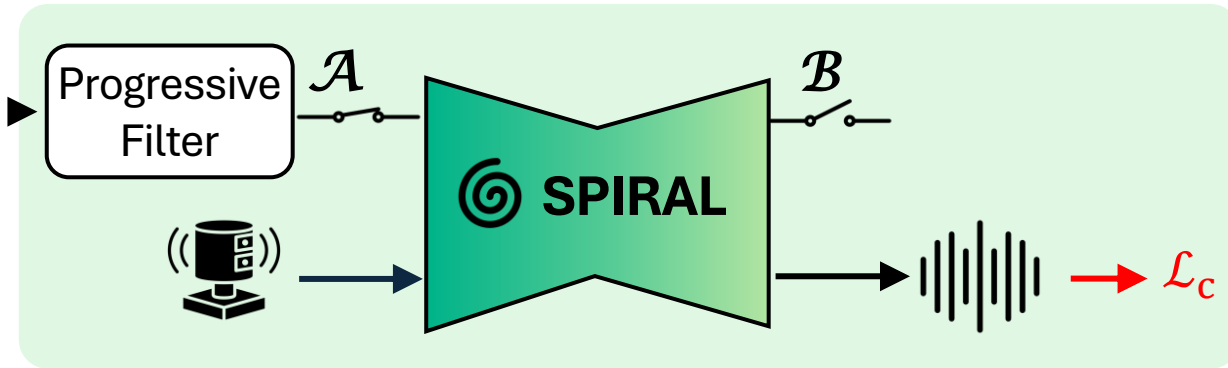


(a) Unconditional Step



(b) Conditional Step



(c) Open-/Closed-Loop Mode Switch



Noisy LiDAR scene  $x_t$



Predicted noise  $\hat{\epsilon}_t$



Predicted seg. label  $\hat{y}_t$



Training & Inference



Training only



Inference only