For each point cloud

§ 3.1: Backbone   Foreground seg.   § 3.3: Motion seg.   § 3.4: Inst. association

$\mathbf{X}^1$

Input points
Offseted points

$\mathbf{X}^2$

§ 3.2: Ego motion

$\mathbf{X}^T$

For each dynamic instance

§ 3.5: Object motion modelling

$\{\mathbf{T}_k^1, \ldots, \mathbf{T}_k^T\}$

Input sequential point cloud

Accumulated point cloud