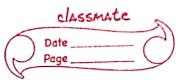
2.4	Object Detection wing LiDAR classmate
	Date Page
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	Step:
- (T)	Ground plane segmentation.
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	uses: a) & segment Ground From Lidag Data and
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	-> signient Ground From Liday Data function the get an
100	-> segment Ground From Lidag Data function the get an estimate of the ground plane.
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	along the direction of the Variate State to fear
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(2)	Semantic Segmentation
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(3)	Bounding Bon fotting.
	-> Nove, each object cluster is fotted in an L-shape bounding bon.
	L-shape bounding bon.
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(A)	Visualization
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الذالخ	> helpert: Object Detection Duplay class: is used the Setrep the Viscoelization windows.
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	2) Detected label generated from Semantis
Actes	2) Detected tabel generated from Semantis Segmentation refuel
•	3) 3D Point Cloud with oriented bounding bones 4) Top Visco of Point Cloud with
	4) Top Visce of Point Cloud with
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(8)-	Loop theologh data. Zdeplay class.
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(6)	Adding tracker
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	-> we use tracker the stabilize the detections.
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	1) Semantic Segmentation 2) Expound plane entraction 3) Clustering & Bounding Son fitting 4) Conversation of detections intre object detection Class Object.
	2) Exercise plane entrailion
	3) Clustering & Bounding bon Atting
	2) Conversation of detection in the object
	detection class Object.
	5) Frain function to be Called. L'Et Call all the Function 3
	LET call all the Function 4
	-> getObject Detection & Maly function.
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