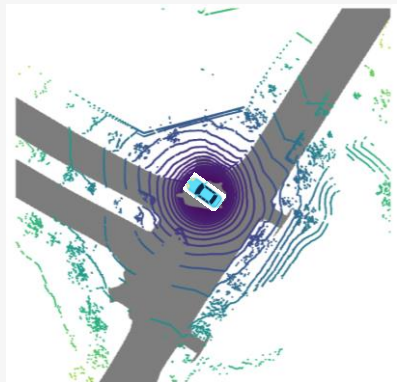
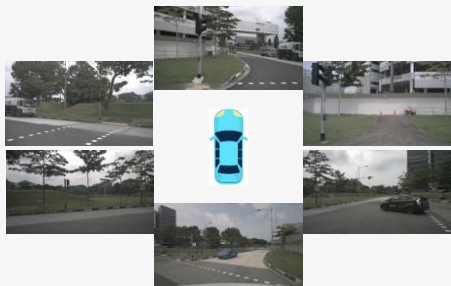


LiDAR Point Cloud

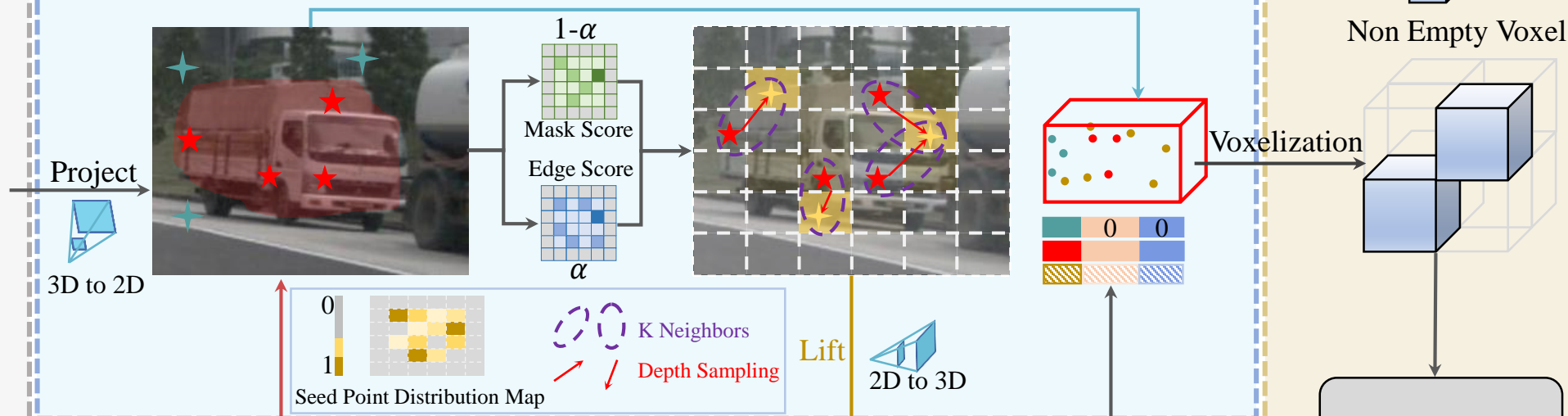


Multi-view Camera Images

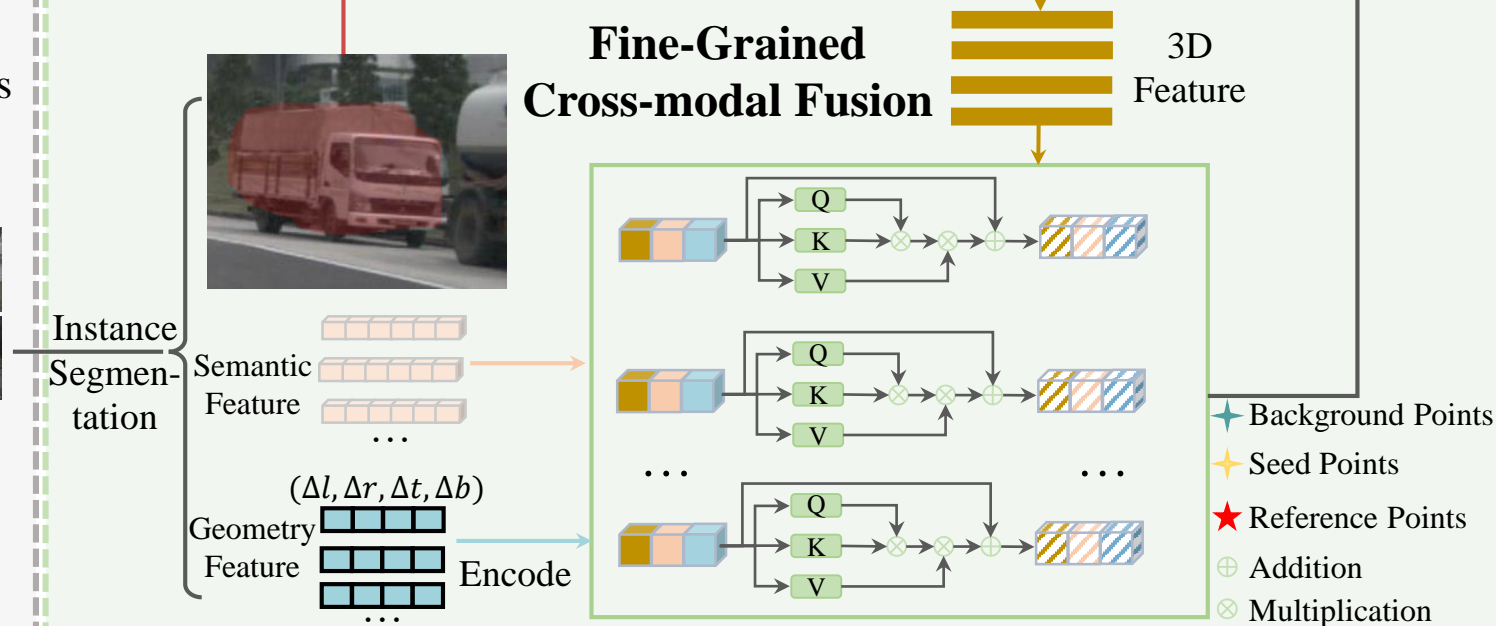


Input Data

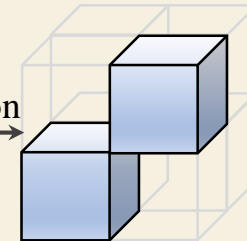
Hybrid Sampling Method



Fine-Grained Cross-modal Fusion

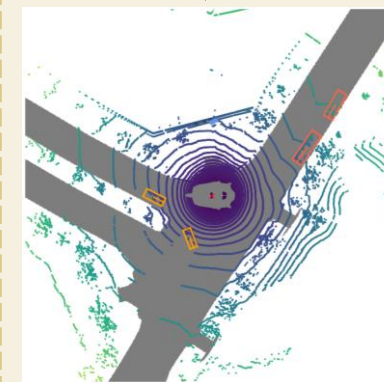


Non Empty Voxel



Detector

Predict



Output Prediction

- Background Points
- Seed Points
- Reference Points
- ⊕ Addition
- ⊗ Multiplication