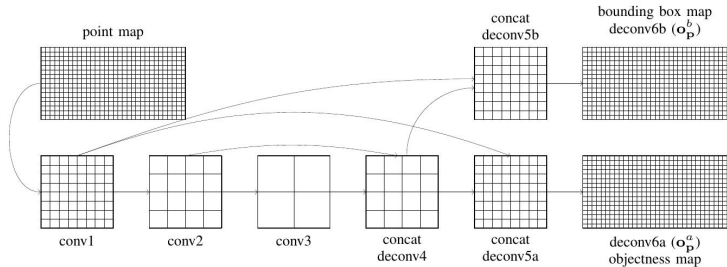# Vehicle Detection from 3D Lidar Using Fully Convolutional Network
B. Li, T. Zhang and T. Xia (RSS 2016)

- Transferring fully convolutional network techniques to the vehicle detection task from the range data of Velodyne Lidar
- Representing the data in a 2D point map
- Using single 2D end-to-end fully convolutional network to predict the objectness confidence and bounding box simultaneously
- Bounding box encoding allows to predict full 3D bounding boxes even with 2D CNN
- State-of-the-art performance on KITTI dataset