

Project 2: Building Built in Minutes: Phase 2

NeRF

Dhrumil Kotadia
Robotics Engineering Department
Worcester Polytechnic Institute
Worcester, Massachusetts

Dhiraj Kumar Rouniyar
Robotics Engineering Department
Worcester Polytechnic Institute
Worcester, Massachusetts

INTRODUCTION

In this report, we will provide a comprehensive analysis of our implementation of the NeRF network. NeRF, short for Neural Radiance Fields, embodies a sophisticated framework encapsulated within a fully connected network architecture. This neural network operates seamlessly, with its input characterized by a unified continuous 5D coordinate system, encompassing spatial positions denoted by (x, y, z) , coupled with viewing directions represented by (θ, ψ) and provides the volume density and the RGB pixel values corresponding precisely to the provided viewing direction as outputs. We use the lego and the ship dataset from the official dataset obtained from the original author.

NeRF uses classical volume Rendering techniques where we consider each point to be a ray that starts from the camera center and passes through the pixel to the world. Let's talk about the premise of the paper. You have images of a particular scene from a few specific viewpoints. Now you want to generate an image of the scene from an entirely new view. This problem falls under novel image synthesis. The immediate solution to novel view synthesis that comes to our mind is to use a Generative Adversarial Network (GAN) on the training dataset. With GANs, we are constraining ourselves to the 2D space of images. The immediate solution to novel view synthesis that comes to our mind is to use a Generative Adversarial Network (GAN) on the training dataset. With GANs, we are constraining ourselves to the 2D space of images. Next question asked is "Why not capture the entire 3D scenery from the images itself?" We are now looking at a transformed problem statement. From novel view synthesis, we have transited to 3D scene capture from a sparse set of 2D images.

This new problem statement will also serve as a solution to the novel view synthesis problem. How difficult is it to generate a novel view if we have the 3D scenery at our hands? Note that, NeRF is not the first to tackle this problem. Its predecessors have used various methods, including Convolutional Neural Networks (CNN) and gradient-based mesh optimization. However, according to the paper, these methods could not scale to better resolution due to higher space and time complexity. NeRF aims at optimizing an underlying

continuous volumetric scene function.

BACKGROUND AND DATASET STRUCTURE

Imagine this. You are out with your camera and spot a beautiful flower. You think about the way you want to capture it. Now it is time to orient the camera, calibrate the settings, and click the picture. This entire process of transforming the world scene into an image is encapsulated in a mathematical model commonly called the forward imaging model. We can visualize the model in Figure 1.

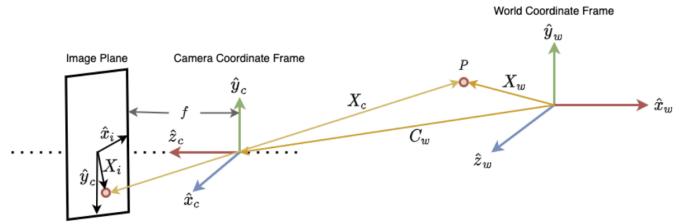


Fig. 1. Forward Imaging Model

The forward imaging model starts from a point in the world coordinate frame. We then transform this to the camera coordinate frame using coordinate transformation. After that, we use projection transformation to transform the camera coordinates onto the image plane.

After unzipping the dataset, you will find three folders containing images: train, val and test and three files containing the orientation and position of the camera: transforms_train.json, transforms_val.json and transforms_test.json. The json file has two parent keys called camera_angle_x and frames. We see that camera_angle_x corresponds to the camera's field of view, and frames are a collection of metadata for each image (frame). Each frame is a dictionary containing two keys, transform_matrix and file_path. The file_path is the path to the image (frame) under consideration, and the transform_matrix is the camera-to-world matrix for that image.

METHOD

We begin with a sparse set of images and their corresponding camera metadata (orientation and position). Next, we want to achieve a 3D representation of the entire scene. The steps for NeRF can be visualized in the following

steps:

- Generate Rays: In this step, we march rays through each pixel of the image.
- Generate Sample points: In this step we sample points ($a_1, a_2, a_3, \dots, a_n$) on the rays. We must note that these points are located on the rays, making them 3D points inside the box. This is done for each batch before providing as an input to the network.
- Positional Encoding: Positional Encoding is a popular encoding format used in architectures like transformers. This paper[2] suggest that deep networks are biased toward learning low-frequency functions. To bypass this problem NeRF proposes mapping the input vector (x, y, z, θ, ϕ) to a higher dimensional representation. Since the 5D input space is the position of the points, we are essentially encoding the positions from which it gets the name.
- Deep Learning: We pass these points into an Multi-Layer Perceptron (MLP) and predict the color and density corresponding to that point.
- Volume Rendering: Let's consider a single ray and send all the sample points to the MLP to get the corresponding color and density. After we have the color and density of each point, we can apply classical volume rendering to predict the color of the image pixel through which the ray passes.
- Photometric Loss: The difference between the predicted color of the pixel and the actual color of the pixel makes the photometric loss. This eventually allows us to perform backpropagation on the MLP and minimize the loss.

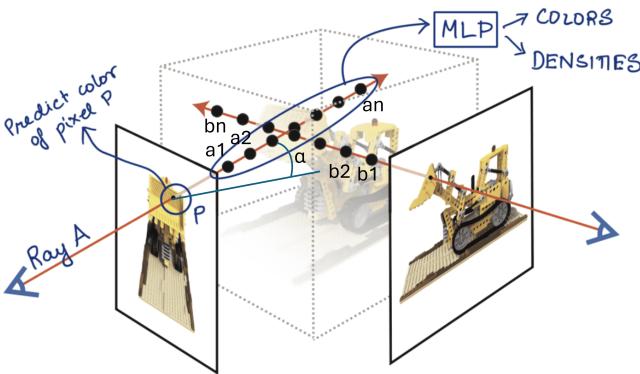


Fig. 2. Rays passing through the image and traversing the 3D scene

RAY GENERATION

As discussed in previous section, we generate rays passing through each pixels. These rays, defined by their origins (camera positions) and directions (pixel coordinates), serve as probes into the scene's volumetric structure. By systematically

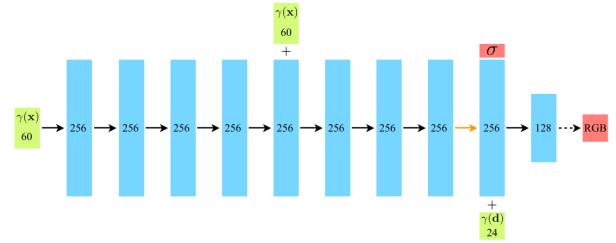


Fig. 3. NeRF Network

sampling along these rays at discrete intervals, NeRF gathers information about the scene's geometry and appearance. This comprehensive sampling strategy enables NeRF to reconstruct intricate details and capture subtle nuances within the scene, facilitating the synthesis of realistic and immersive visualizations. We have specified the near and far bounds as 2 and 6 respectively, to form a cube inside which the 3D structure lies. For training, we have considered 256 sample points on each ray lying between the near and far bounds. After getting these samples, we perturb the samples a little randomly which enables us to have a more even spread throughout the ray. These sample points are then passed to the model.

NETWORK

We have used the network mentioned in the official NeRF paper [1] but we have only used one network instead of both coarse and fine networks. The architecture can be seen in figure 4. The implementation is a fully connected network and has hidden layers with 256 channels each and a ReLU after it. After 4 layers, there is a skip connection that concatenates the input to the fifth layer. An additional layer outputs the density and is then concatenated with the viewing direction. It is then processed by an additional fully connected layer with 128 channels which gives the RGB output. For dataloading, we read all the images of the train or test set provided and convert them to a lower resolution (200,200) for faster computation. We then generate rays for all the images, convert them to 2D tensors and provide them to the torch dataloader which will provide all the values according to the batch size as an input for the network. In the network, firstly, all sample points are calculated for each ray provided by the dataloader, positional encoding is done and then the data is given to the network. The MSE loss function is used to calculate the loss based on the output generated by the network. Renderer is used to render the output generated by the network.

- Number of samples per ray: 256
- Learning rate: 0.0005
- Optimizer: Adam
- Loss: MSE loss
- Near, Far bounds: 2, 6

OUTPUTS

The Peak signal to noise ratio (PSNR) and Structural index similarity (SSIM) are the two measuring tools that are widely

```

Avg PSNR: 18.111887
Avg SSIM: 0.4986792
Done
100%|

```

Fig. 4. Average PSNR and SSIM Results on Test set

used in image quality assessment. The values obtained after 10 Epochs (resource constraint) are shown in figure 4. Also the data are listed in the table below.

TABLE I
PHOTOMETRIC LOSS

Method	Loss
Peak signal to noise ratio (PSNR)	18.11
Structural index similarity (SSIM)	0.49

The outputs of the Test set for the Lego dataset can be seen in figure 5. The rendered images are compared with the ground truth and it is evident that the network does an adequate job of reproducing the novel views.

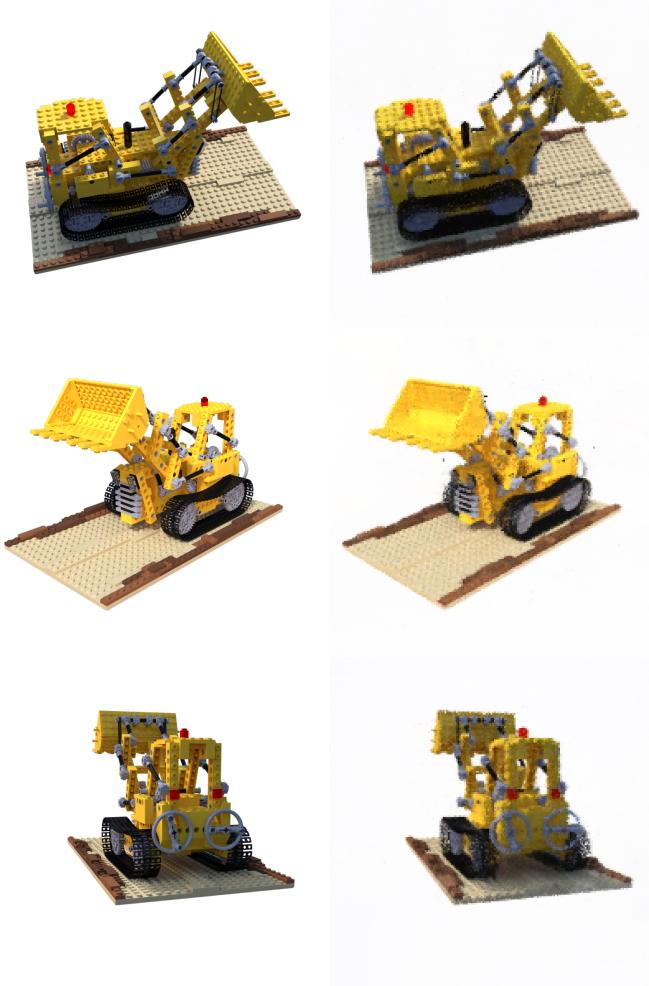


Fig. 5. Ground Truth (Left) and Rendered Image(Right)

However, this is done using positional encoding. Without

positional encoding, the outputs are less than desirable as can be seen in figure 6.

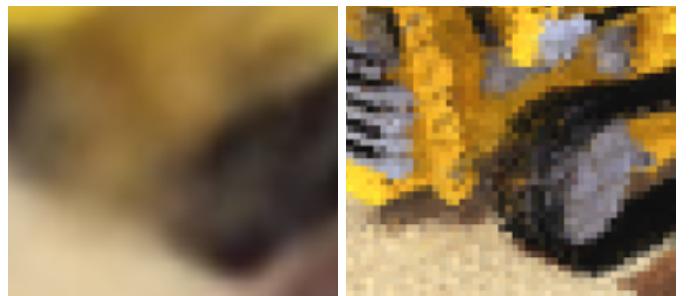


Fig. 6. Rendered images without positional encoding(left) and with positional encoding(Right)

The output images for the ship dataset are shown in figure 7.



Fig. 7. Ground Truth(Left) and Rendered Image(Right)

OBSERVATIONS:

An observation is that with the same pretrained model, when the test images are queried with different sample points per rays, the output changes drastically. This can be seen in figure 8.

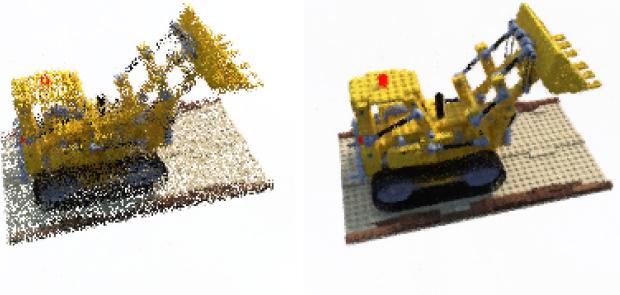


Fig. 8. Rendered images with 32 sampling points(left) and 128 sampling point(right) per ray

Another observation is that there are some rendered images which has artifacts that are undesirable. These can be seen in figure 9.



Fig. 9. Bad rendering of images with artifacts

Overall, looking at the Lego and the Ship rendered outputs, it can be seen that the result are adequate but can be improved. There are 2 main improvements that can be done here.

- 1) The image resolution is reduced to (200,200) from the original (800,800). This is done to reduce the training time but as a result of this, the output resolution is less so the image does not have the sharpness and clarity that is expected.
- 2) The training can be done for more epochs to improve the output and get to get rid of the artifacts that have been generated.

CONCLUSION:

It can be concluded that the NeRF network can generate the novel views based on the input train images and can generate a gif of the object in consideration in 3D. NeRF is an example of groundbreaking research in both Deep Learning and Computer Graphics. It advances the field a great deal by achieving results that very few methods have been able to do thus far.

REFERENCES

- [1] B. Mildenhall, P. Srinivasan, M. Tancik, J. Barron, R. Ramamoorthi, and R. Ng. Nerf: Representing scenes as neural radiance fields for view synthesis. 2020.
- [2] N. Rahaman, A. Baratin, D. Arpit, F. Draxler, M. Lin, F. A. Hamprecht, Y. Bengio, and A. Courville. On the spectral bias of neural networks, 2019.