POINTNET++: DEEP HIERARCHICAL FEATURE LEARNING ON POINT SETS IN A METRIC SPACE

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INTRODUCTION

- Context: Analyzing geometric point sets, such as those from 3D scans, is crucial for applications like autonomous vehicles.
- **Challenges:** Point clouds must be invariant to permutations, and their local structures vary due to factors like scanning density.
- Prior Work: PointNet directly processes point sets but lacks the ability to capture local geometric structures effectively.
- Our Approach: Introducing PointNet++, a hierarchical network that processes points in a metric space to capture fine to coarse geometric structures.

INTRODUCTION (CONT'D)

 Design Goals: PointNet++ uses overlapping local regions and a recursive application of PointNet to abstract point features hierarchically.

Unique Aspects:

- Overlapping partitions defined by a farthest point sampling (FPS)
 algorithm to ensure coverage.
- Multi-scale neighborhood processing to handle non-uniform densities effectively.
- Advantages: Adapts to data and metric, ensuring efficient and effective feature extraction compared to traditional CNN approaches.

PROBLEM STATEMENT

- **Metric Space Definition:** $\mathcal{X} = (M, d)$ where $M \subseteq \mathbb{R}^n$ and d is the distance metric derived from Euclidean space.
- **Challenge:** Non-uniform density of *M* in ambient space, impacting the effectiveness of local pattern learning.
- **Goal:** Develop function f that can process \mathfrak{X} to produce semantic outputs, such as classification or segmentation.
- Relevance: Understanding and processing the varying densities and scales of point sets to extract meaningful semantic information.

REVIEW OF POINTNET

- PointNet processes unordered point sets directly, approximating any continuous set function.
- Uses a multi-layer perceptron (MLP) to encode spatial information of each point.
- Aggregates features using a max pooling operation, ensuring permutation invariance.

HIERARCHICAL POINT SET FEATURE LEARNING

- Builds a hierarchical grouping of points to abstract local regions progressively.
- Integrates multiple levels of set abstraction:
 - Sampling layer selects centroids via farthest point sampling (FPS).
 - Grouping layer forms local regions around these centroids.
 - PointNet layer encodes local regions into feature vectors.

ROBUST FEATURE LEARNING UNDER NON-UNIFORM SAMPLING

- PointNet++ uses multi-scale grouping (MSG) and multi-resolution grouping (MRG) to handle varying densities.
- Adapts to local density changes, improving robustness and detail capture:
 - MSG captures multiple scales simultaneously.
 - MRG combines features across different resolutions.

FEATURE PROPAGATION FOR SET SEGMENTATION

- Hierarchical feature propagation strategy interpolates features from sampled to original points.
- Inverse distance weighting ensures smooth feature transition across points.
- Combines interpolated and directly linked features for enhanced context:

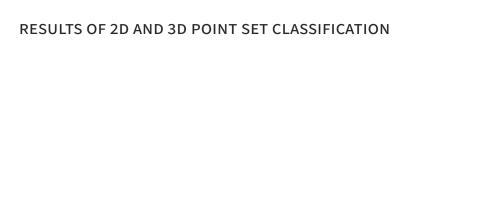
$$f^{(j)}(x) = \frac{\sum_{i=1}^{k} w_i(x) f_i^{(j)}}{\sum_{i=1}^{k} w_i(x)} \quad \text{where} \quad w_i(x) = \frac{1}{d(x, x_i)^p}, \ j = 1, ..., C \quad (1)$$

OVERVIEW OF DATASETS

- MNIST: 60k training and 10k testing samples of handwritten digits.
- ModelNet40: 9,843 training and 2,468 testing samples of 3D CAD models.
- SHREC15: 1,200 shapes from 50 categories, using five-fold cross-validation.
- ScanNet: 1,513 scanned and reconstructed indoor scenes with 1,201 for training and 312 for testing.

CLASSIFICATION EXPERIMENTS ON MNIST AND MODELNET40

- Evaluated on MNIST (2D) and ModelNet40 (3D).
- MNIST: Images converted to 2D point clouds.
- ModelNet40: 3D point clouds sampled from mesh surfaces.
- Networks trained with 512 points for MNIST and 1024 points for ModelNet40.
- Additional features (normals) and more points used for higher performance.



EVALUATING ROBUSTNESS TO POINT DENSITY VARIATION

- Tested robustness by randomly dropping points during test.
- Demonstrated strong performance despite reduced point density.
- Multi-scale and resolution strategies maintain high accuracy.

SEMANTIC SCENE LABELING ON SCANNET DATASET

- Goal: Predict semantic labels for points in indoor scans.
- Compared with baselines on the ScanNet dataset.
- Hierarchical feature learning captures multi-scale geometric features.

VISUALIZATION OF FEATURE LEARNING ON 3D POINT CLOUDS

- Visualization of learned 3D point cloud patterns from ModelNet40.
- Illustrates the network's ability to recognize various geometric features.