

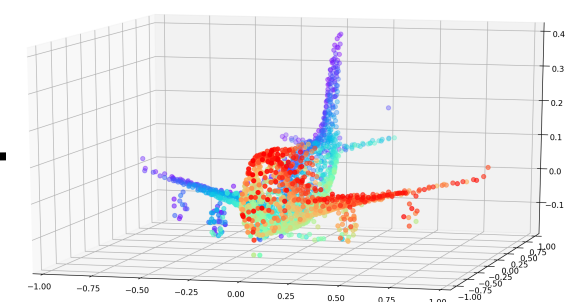
Input point cloud S

$N \times 3$

Shape reconstruction loss (Chamfer distance)

Output point cloud \hat{S}

$M \times 3$



Decoder

