Point Cloud Sampling Network

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1 Abstract

The increasing number of points in 3D point clouds has brought great challenges for subsequent algorithm efficiencies. Down-sampling algorithms are adopted to simplify the data and accelerate the computation.

2 Introduction

Existing works [4, 1, 2] often use random sampling and the farthest point sampling (FPS) to down-sample the point clouds.The differences between our work and former learning-based works are presented in Fig. 1.The discrepancy between progress-net and our method is presented in Fig. 1-(b) and (c).

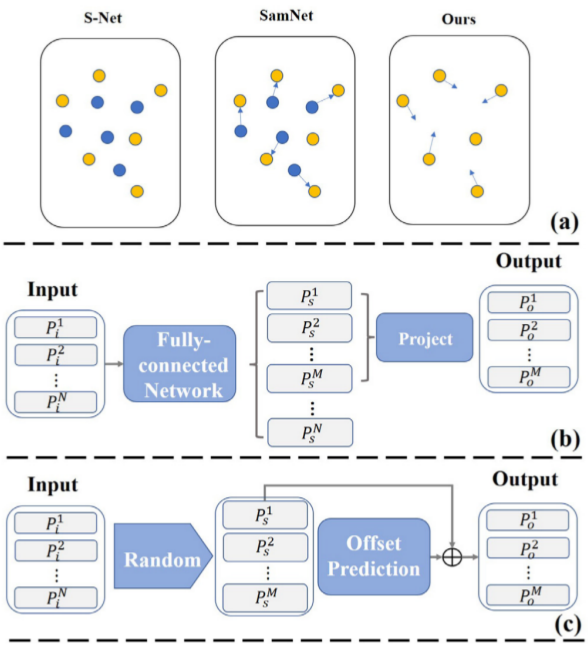

Figure 1: (a) shows the differences between learning-based sampling strategies, while (b) and (c) present the discrepancy between progress-net and our method in multiresolution sampling

Our contributions can be summarized as:

- We propose a novel learning-based point cloud sampling framework named fast sampling network (FPN) by driving existing randomly sampled points to better positions;
- We introduce a hybrid training strategy to help FPN adapt to different sampling resolutions by randomly introducing selecting the resolution of initial points during training;

3 Methodology

3.1 Basic Pipeline

The basic pipeline of FPN is presented in Fig. 2. We aggregate global features from the input points with a set of multilevel perceptions (MLPs) and Max Pooling following PointNet [3]

3.2 Hybrid Training Strategy

The achievement of HTS is presented as Algorithm 9.

3.3 Loss function

The range constraint can be presented as

$$\mathcal{L}_{rc} = \frac{1}{N}\sum ||S_o - S_i||_2 \tag{1}$$

For reconstructionrelated tasks, it may be Chamfer Distance or Earth Mover Distance [22] defined as

$$\begin{aligned}\mathcal{L}_{task} &= L_{CD}(S_1, S_2)\\ &= \frac{1}{2}\left(\frac{1}{|S_1|}\sum_{x\in S_1} min_{y\in S_2})||x-y||_2 + \frac{1}{|S_2|}\sum_{x\in S_2} min_{y\in S_1}||x-y|\end{aligned} \tag{2}$$

or

$$\mathcal{L}_{task} = \mathcal{L}_{EMD}(S_1, S_2) = min_{\phi;S_1\rightarrow S_2}\frac{1}{|s_1|}\sum_{x\in S_1}||x-\Phi(x)||_2 \tag{3}$$

4 Experiments

4.1 Dataset and Implementation Details

Table 1: The number of neurons in networks. f_1, f_2, f_3 are modules in Fig. 2.

	f_1	f_2	f_3
MLPs	(128,256,256)	(128,256,256)	(128,128,3)

Table 2: The comparison on optimal clustering.

Center	Iterations	1	10	100
16	FPS	2.43	2.00	1.98
	Ours	2.16	1.98	1.96
32	FPS	1.20	1.02	1.00
	Ours	1.11	1.00	1.00

The hyper-parameter λ is tuned on the validation split of ShapeNet.Detailed network structures are shown in Table 1

4.2 Discussion and Clustering

Except down-stream tasks such as reconstruction or recognition, down-sampled points can also be adopted as the initial clustering centers. The results are presented in Table 2.

4.3 Ablation Study

The influence of range constraint. Note that this is only conducted to observe the influence of range constraint weight λ on sampling performances instead of the tuning of λ, which is chosen according to the val set introduced in Section 4.1.

Algorithm 1: Training with Hybrid Training Strategy

Input: data X, the number of iterations $iter$, the number of resolutions m;

$prob_1, prob_2, \ldots, prob_m = \frac{1}{m}, \frac{1}{m}, \ldots, \frac{1}{m}$;

for $i = 1$ **to** $iter$ **do**

  Select the resolution r according to $prob_1, \ldots, prob_m$;

  Train FPN by descending gradient:$\Delta_{\theta_{FPN}} \mathcal{L}_{loss} \left(Y_{X,r}\right)$

end

References

[1] Qingyong Hu et al. "Randla-net: Efficient semantic segmentation of large-scale point clouds". In: *Proceedings of the IEEE/CVF conference on computer vision and pattern recognition*. 2020, pp. 11108–11117.

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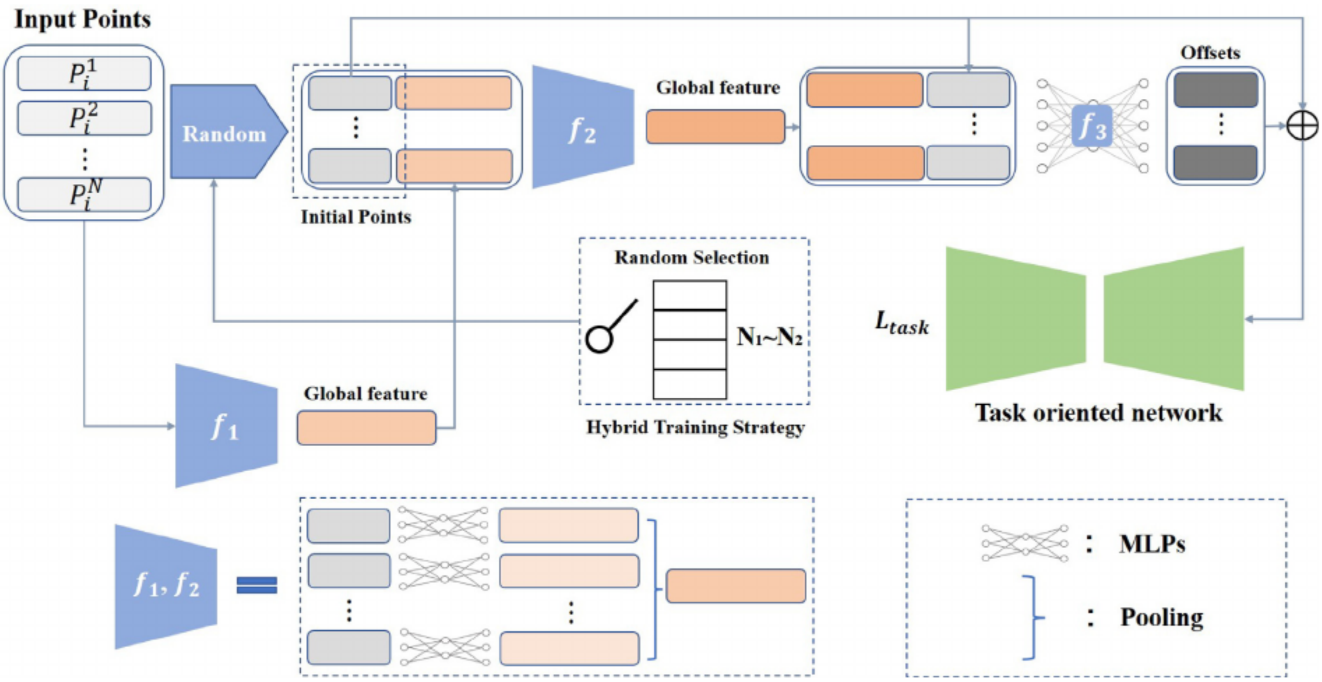

Figure 2: The whole pipeline of FPN. The + denotes element-wised addition. f_1 and f_2 aggregate features by MultiLayer Perceptrons(MLPs) and pooling, while f_3 is a group of MLPs to predict offsets from coordinates and features. The task network is corresponding to the specific task, such as point cloud recognition and reconstruction. L_{task} is the loss constrained the task network.