

Plan for 3D Deep

Jungwon Kang, Maryam Jameela, Razieh Ramak

Sept 30 2018

Objectives

- Building 1st Version Deep Network for Each Task

Task	Major Contributor	Objectives
Noise filtering (for Optech)	Razieh Ramak	Point cloud segmentation (Noise/Non-noise), non real-time
Point cloud segmentation (for Optech)	Maryam Jameela	Point cloud segmentation (N-class objects), non real-time
3D object detection (for Thales)	Jungwon Kang	Real-time 3D object detection

Schedule

Month	Task	Deliverable
Oct 2018	<ul style="list-style-type: none"> • Problem definition • Dataset preparation • Literature survey 	<ul style="list-style-type: none"> • Document describing problem definition, dataset, and literature survey • Visualization of dataset
Nov	<ul style="list-style-type: none"> • Practicing deep library • Design & implementation 	<ul style="list-style-type: none"> • Document describing design
Dec	<ul style="list-style-type: none"> • Implementation 	<ul style="list-style-type: none"> • Source code (Dec 31)
Jan 2019	<ul style="list-style-type: none"> • Documentation 	<ul style="list-style-type: none"> • Document describing implementation (Jan 15)

*Submission deadline of major conferences starts from March.

Management Policy

- Regular meeting or discussion biweekly
- Team website:
 - <https://github.com/yorku-ausml/deep3d>

To-do List

- Problem definition, including
 - Cause of noise (Razieh)
 - Object classes (Maryam, Jungwon)
- Dataset description, including
 - Existing Optech airborne dataset (Razieh)
 - Dataset size
 - Current repository
 - Visualization
- Etc
 - Finding point cloud label tool (for making ground-truth)
 - Finding visualization tool

Key Literature

■ Point cloud segmentation

- Large-scale point cloud segmentation with superpoint graphs
https://github.com/loicland/superpoint_graph
*Rank 1 in <http://www.semantic3d.net/>
- PointNet++: deep hierarchical feature learning on point sets in a metric space
<https://github.com/charlesq34/pointnet2>
*Rank 4 in <http://www.semantic3d.net/>

■ Object detection


- Joint 3D proposal generation and object detection from view aggregation
<https://github.com/kujason/avod>

*Literature list is also available at <https://github.com/yorku-ausml/deep3d/wiki/Related-works>

Current Progress

Oct 12 2018

Asana Assignment

Semantic Labeling - Teledyne Optech ☆ ...  [Share](#)


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Backlog ▾

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3rd Stage - SVM ▾

 Oct 19

2nd Stage - feature extraction ▾


 Friday

1st Stage - noise filtering with hard-constraint based on spatial proximity. ▾


Prioritized ▾

+

Understand PCL and voxelization ▾

 Oct 5

Summarize Leihan's works with Razieh's view ▾

 Oct 1

Progress on Noise Filtering

Razieh

■ Atmospheric noise filtering

- Noise filtering
Segmentation of raw point cloud using voxelization
Pre-classification by defining special rules
- Feature extraction
Using Eigen library and programming
- Classification using SVM
Using "libSVM"

■ Understanding PCL and voxelization

- PCL
A large scale, open project for 2D/3D image and point cloud processing. However, there is no PCL in noise filtering application
- Voxelization
A data structure used to represent a collection of multi-dimensional points and is commonly used to represent three-dimensional data

Clarifying the Task

Dataset used for training?
What kind of dataset will be used? Mobile data / airborne lasers / hybrid dataset mixture of both.
What kind of environment? Indoor / Outdoor or Urban / Rural / Forest
Which object classes?

Key Papers

■ Point cloud segmentation

- PointNet: Deep Learning on Point Sets for 3D Classification and Segmentation

<https://github.com/charlesq34/pointnet>

*Both used in the two following papers

- PointNet++: deep hierarchical feature learning on point sets in a metric space

<https://github.com/charlesq34/pointnet2>

*Rank 4 in <http://www.semantic3d.net/>

- Large-scale point cloud segmentation with superpoint graphs

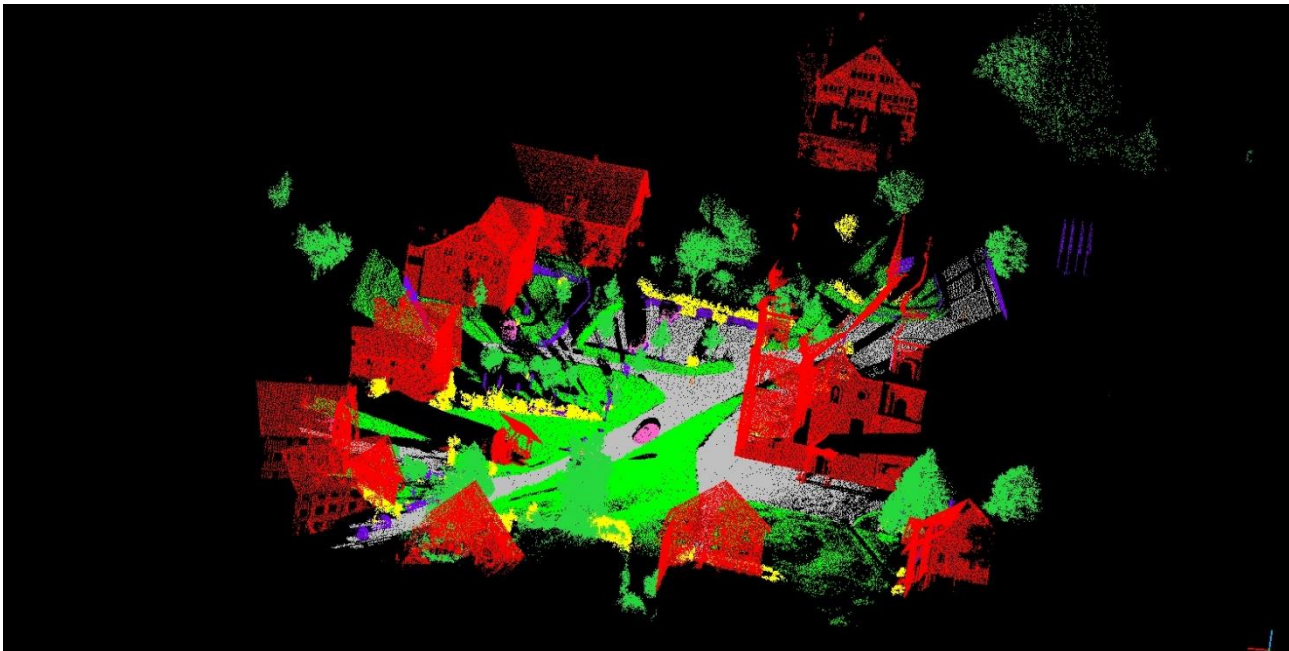
https://github.com/loicland/superpoint_graph

*Rank 1 in <http://www.semantic3d.net/>

Publicly Available Dataset (1/3)

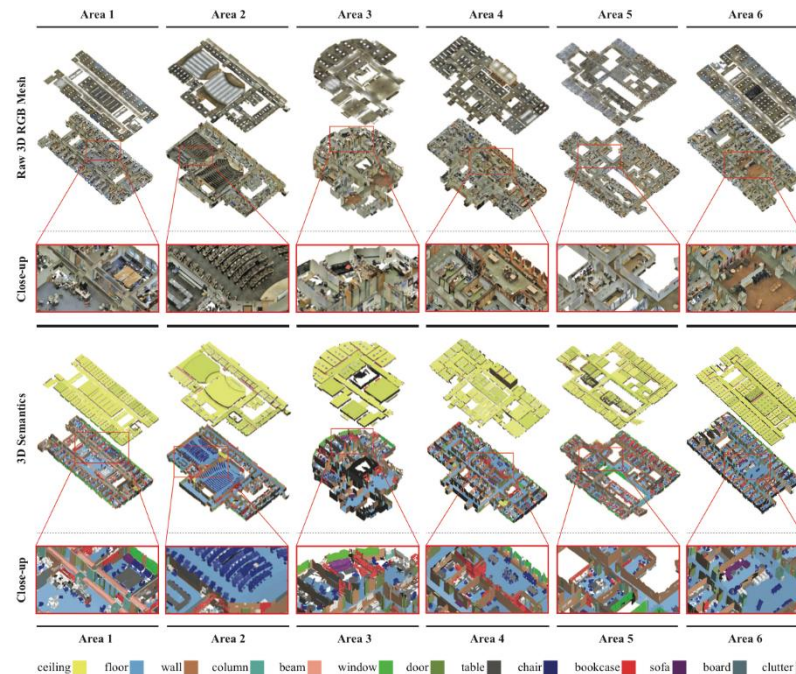
■ Semantic3D

- LiDAR dataset with over 3 billion points from a variety of urban and rural scenes.
- <http://www.semantic3d.net/>
- Managed by ETH (<http://www.prs.igp.ethz.ch/>)
- 8 class labels, namely {1: man-made terrain, 2: natural terrain, 3: high vegetation, 4: low vegetation, 5: buildings, 6: hard scape, 7: scanning artefacts, 8: cars}.



Publicly Available Dataset (2/3)

- S3DIS (Stanford Large-Scale 3D Indoor Space)
 - 3D RGB point clouds of six floors from three different buildings
 - <http://buildingparser.stanford.edu/dataset.html>
 - Currently, *2D-3D-S dataset* is newly released.
 - 13 object classes (ceiling, floor, wall, beam, column, window, door, and movable elements: table, chair, sofa, bookcase, board and clutter for all other elements)



Publicly Available Dataset (3/3)

■ Etc

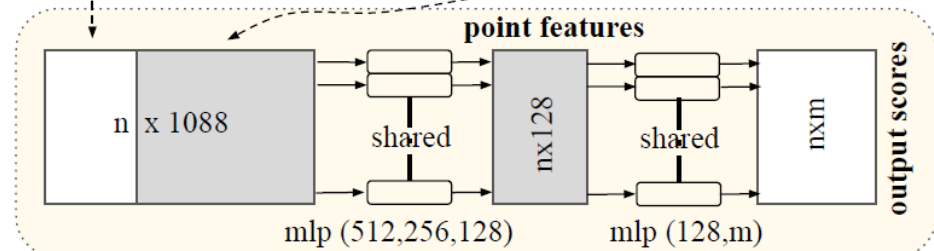
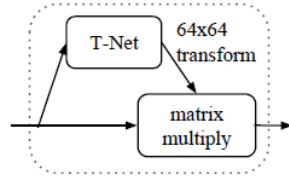
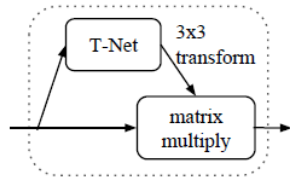
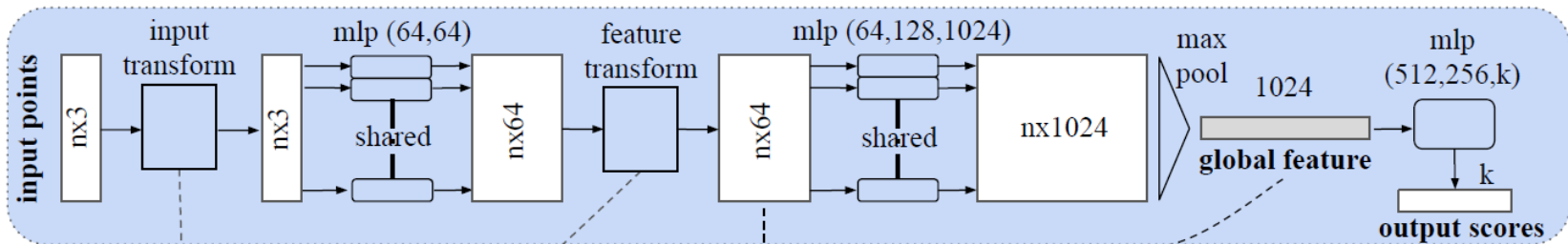
- Oakland 3-D Point Cloud Dataset (2009)
 - http://www.cs.cmu.edu/~vmr/datasets/oakland_3d/cvpr09/doc/
- NYU Depth Dataset V2 (2012)
 - https://cs.nyu.edu/~silberman/datasets/nyu_depth_v2.html
- Sydney Urban Objects data set
 - <http://www.acfr.usyd.edu.au/papers/SydneyUrbanObjectsDataset.shtml>
- IQmulus & TerraMobilita Contest
 - Mobile laser scans (MLS) in dense urban environments
 - <http://data.ign.fr/benchmarks/UrbanAnalysis/>
- Vaihingen3D airborne benchmark
 - <http://www2.isprs.org/commissions/comm3/wg4/3d-semantic-labeling.html>

PointNet

■ Architecture

- <http://stanford.edu/~rqi/pointnet/>

Classification Network

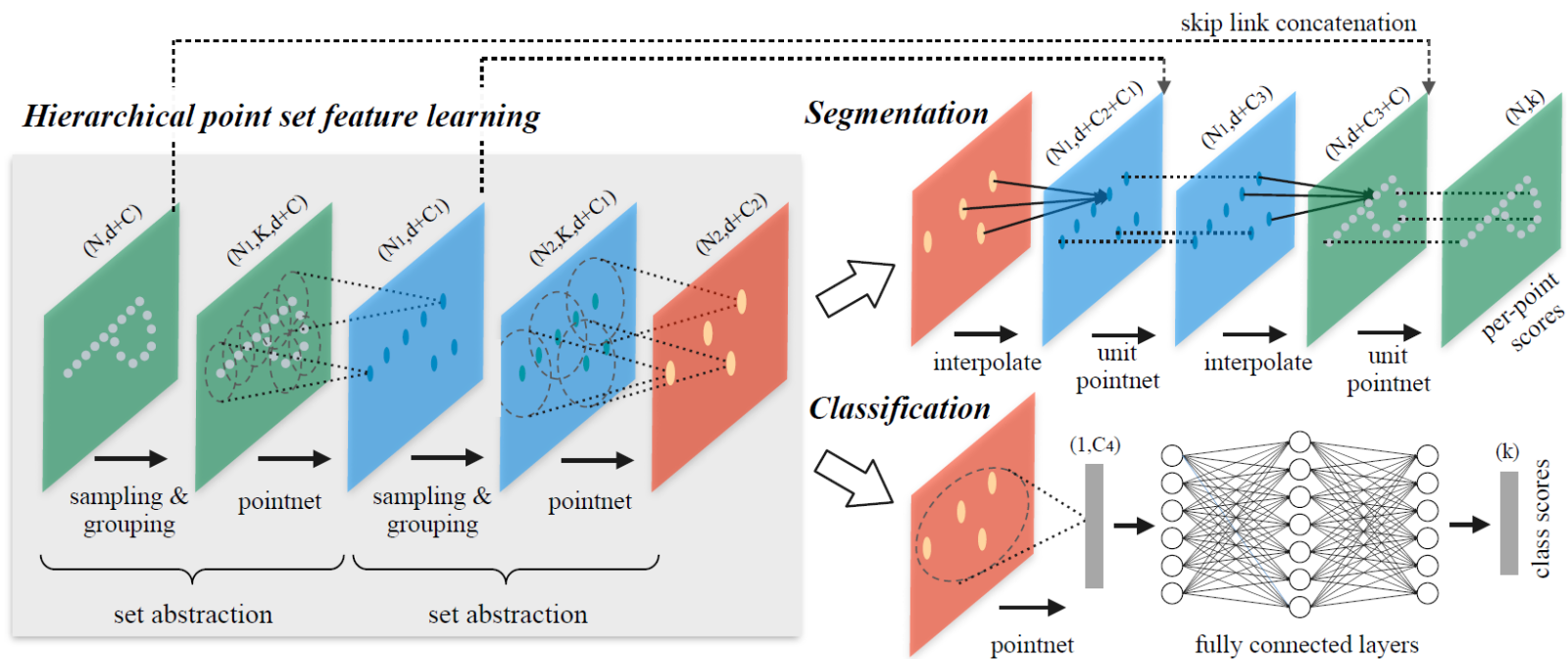


Segmentation Network

PointNet++

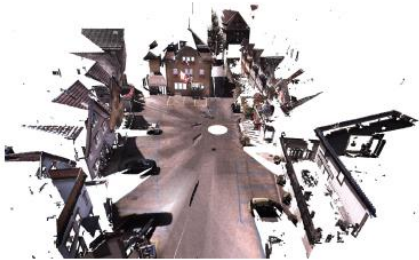
■ Hierarchical Feature Learning Architecture

- <http://stanford.edu/~rqi/pointnet2/>



Superpoint Graph (1/2)

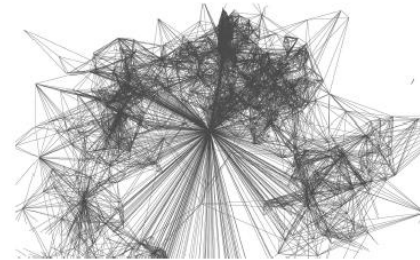
- Individual steps in pipeline



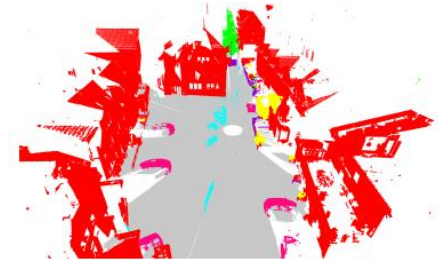
(a) RGB point cloud



(b) Geometric partition



(c) Superpoint graph



(d) Semantic segmentation

Superpoint Graph (2/2)

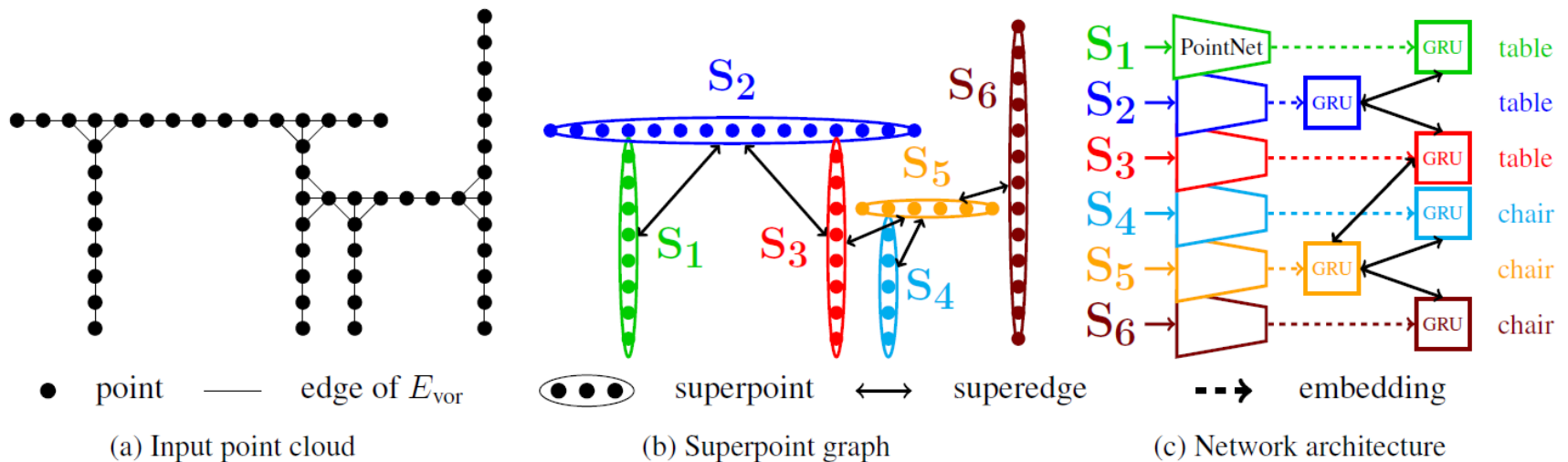


Illustration of our framework on a toy scan of a table and a chair. We perform geometric partitioning on the point cloud (a), which allows us to build the superpoint graph (b). Each superpoint is embedded by a PointNet network. The embeddings are then refined in GRUs by message passing along superedges to produce the final labeling (c).


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Notes

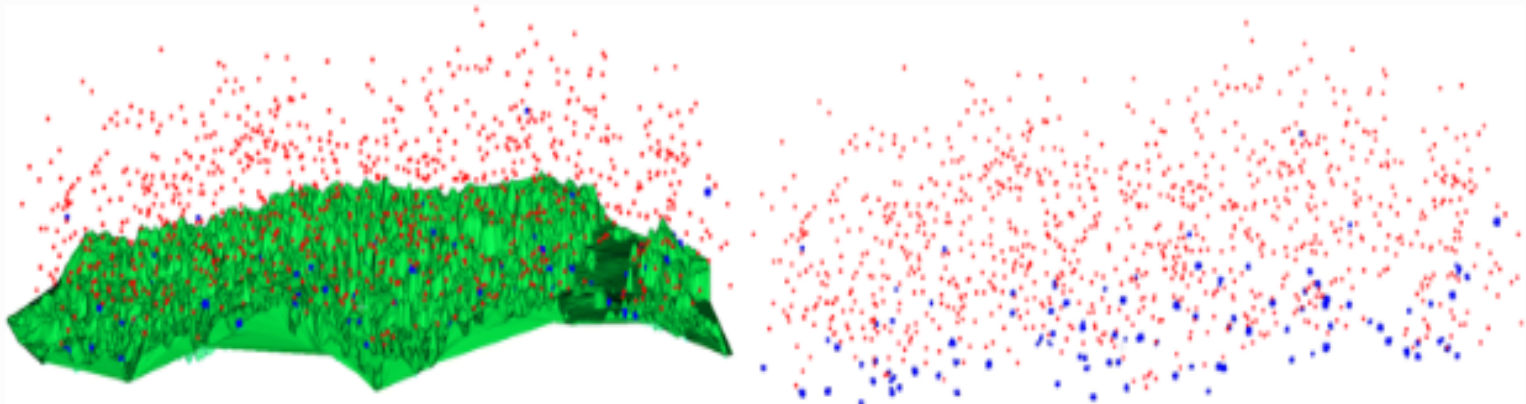
- Summarizing why noise happens, including some figures describing laser pulse and error band, and the terms like PIA and correspondence
- Knowing limitations of PointNet and how PointNet++ solve it
- Checking some parts (in Superpoint graph method) that the hand-crafted things are needed. (e.g. superpoint creation, superedge features)
- Knowing limitations of superpoint graph method
- Understanding how each method deal with object-scale issue and contextual information
- Shenlong Wang's paper
 - Deep Parametric Continuous Convolutional Neural Networks

Noise filtering

LiDAR is a relatively new technology which is an alternative to field surveying and photogrammetric techniques to collect elevation data. This technology is able to provide high accuracy three-dimensional data with reasonable cost and time. 3-D data acquired by this technology are applicable in 3-D urban modeling, DTM generation, mapping and etc. Although LiDAR data present high height accuracy, there are some defects in them leading to some disadvantages in output of next processes. Hence, these errors should be removed before performing any processes. One of the most important errors in LiDAR data is the outlier points. Measured elevation for these points is unreasonably more or less from their neighboring points. The outliers are mainly measurements that do not obey the local surface geometry and do not belong to the topography of the interested area. In some references in the literature, the points with too high elevation values are named "positive outliers" and the points with too low elevation values are named "negative outliers", so we used these terms, too. The outliers can be caused from different sources. Positive outliers are resulted from hitting laser beams to suspended objects at high altitude like atmospheric articles. In connection with the negative outliers, it is believed that the laser beams be reflected several times among the glasses of buildings before they are detected, just like the multi-path effect of GPS. These specular reflections result in a longer travel time of the laser beam, and thus a lower elevation is calculated during post-flight processing. The negative outliers are often located at a few spots beside which there are tall buildings

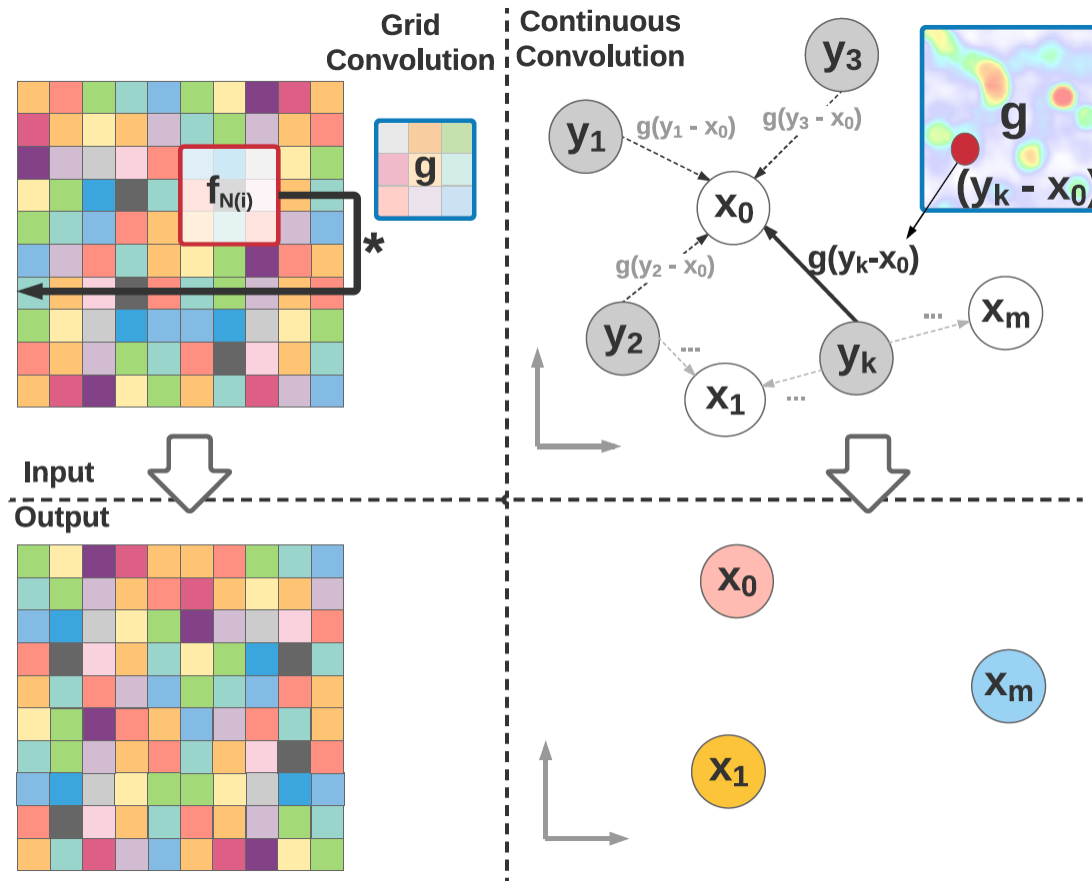
Noise filtering

- Outliers in LiDAR data



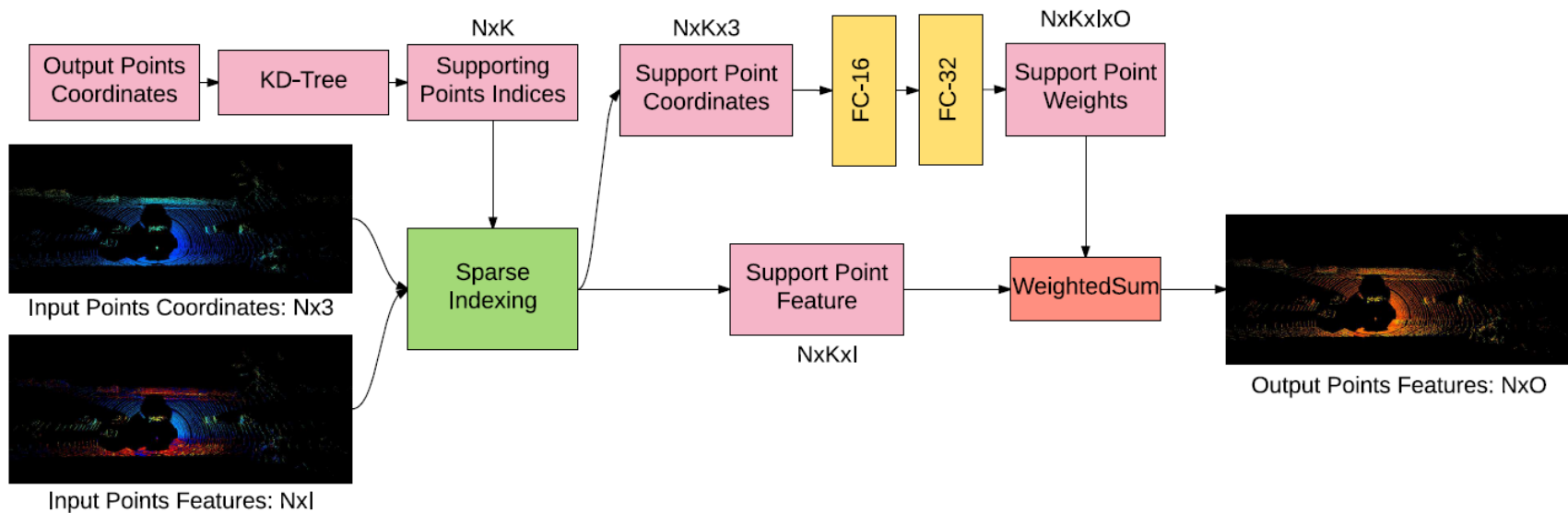
SfM dataset – left: clean DSM surface in green, random unclustered outliers in red, clustered random outliers in blue – right: only outliers

Deep Parametric Continuous CNNs



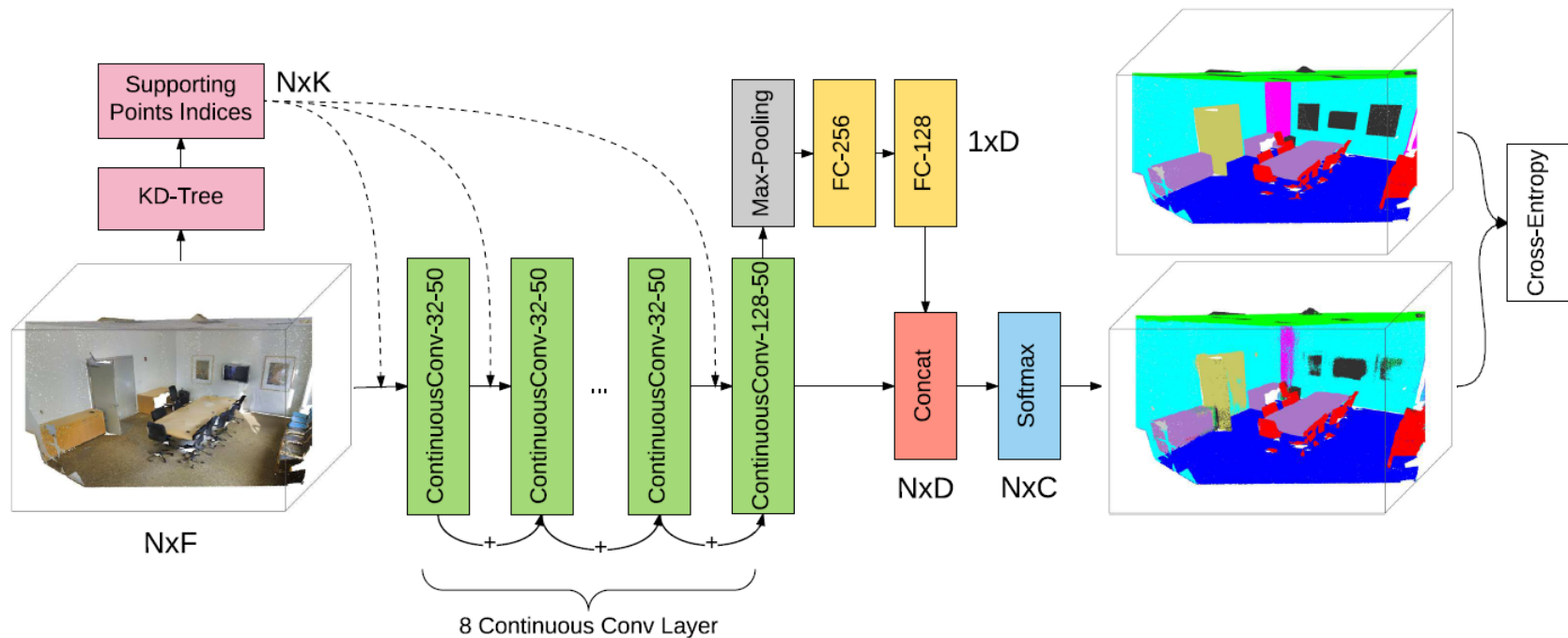
Unlike grid convolution, parametric continuous convolution uses kernel functions that are defined for arbitrary points in the continuous support domain. As a result, it is possible to output features at points not seen in the input.

Deep Parametric Continuous CNNs

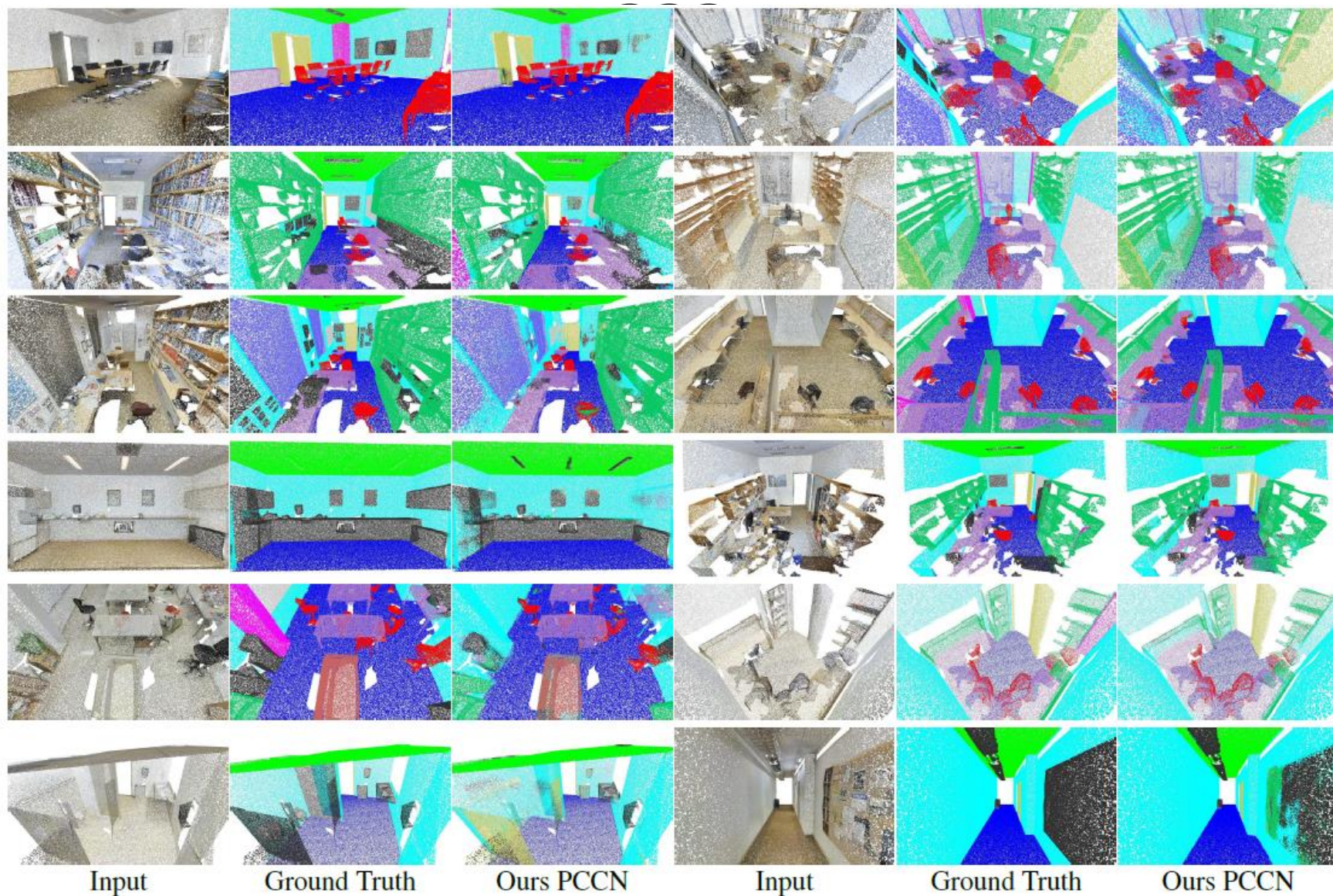


Detailed Computation Block for the Parametric Continuous Convolution Layer

Deep Parametric Continuous CNNs



Architecture of the Deep Parametric Continuous CNNs for Semantic Labeling Task



Semantic Segmentation Results on Stanford Indoor3D Dataset



Ground Truth

3D-FCN

Ours PCCN

Ours 3D-FCN+PCCN

Semantic Segmentation Results on Driving Scene Dataset;
Colored: correct prediction; white: wrong prediction.

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