nD-PointClouds project conclusion and next steps

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Final/year 3 consortium meeting nD-PointClouds, 12 nov'24, Delft

Motivation nD-PointCloud

- point cloud data sets are often used for monitoring
  → dynamic point clouds
  → time added as additional organizing dimension

- organizing point cloud data in levels of Importance (LoI) is an approach to manage large data sets
  → LoI: discrete (multi-scale/dLoI) or continuous (vario-scale/cLoI)
  → scale treated as additional organizing dimension

- how to manage higher dimensional point clouds (4D, 5D, …)?

Overview

- **nD-PointCloud recap**
  - **foundations**
  - **PostgreSQL implementation**
  - **nD Convex polytope query**
  - **Apache Parquet**
  - **change detection**
  - **AHN potree conversions**
  - **VPC/COPC**

- conclusion
  - future work
  - main publications

AHN3 colored by ‘intensity gradient’

nD-PC foundations

ISPRS Journal of Photogrammetry and Remote Sensing 194 (2022) 119–131

ELSEVIER

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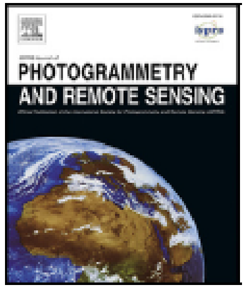
ISPRS Journal of Photogrammetry and Remote Sensing

journal homepage: www.elsevier.com/locate/isprsjprs



Check for updates

Organizing and visualizing point clouds with continuous levels of detail

Peter van Oosterom [a,*], Simon van Oosterom [b], Haicheng Liu [c], Rod Thompson [a], Martijn Meijers [a], Edward Verbree [a]

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ARTICLE INFO

Keywords:
nD point clouds
Continuous level of detail (cLoD)
Space Filling Curve (SFC)
Perspective view selection

ABSTRACT

Point clouds contain high detail and high accuracy geometry representation of the scanned Earth surface parts. To manage the huge amount of data, the point clouds are traditionally organized on location and map-scale; e.g. in an octree structure, where top-levels of the tree contain few points suitable for small scale overviews and lower levels of the tree contain more points suitable for large scale detailed views. The drawback of this solution is that it is based on discrete levels, causing visual artifacts in the form of data density shocks when creating

cLoI computation, getting rid of discrete levels → real continuous levels, nD case

- for ideal continuous distribution function over levels (nD):

$$f(l,n) = \frac{2^{(n-1)l}(n-1)\ln 2}{2^{(n-1)(L+1)}-1}$$

for l between 0 and $L+1$
and n number of dimensions

- this function has Cumulative Distribution Function (CDF):

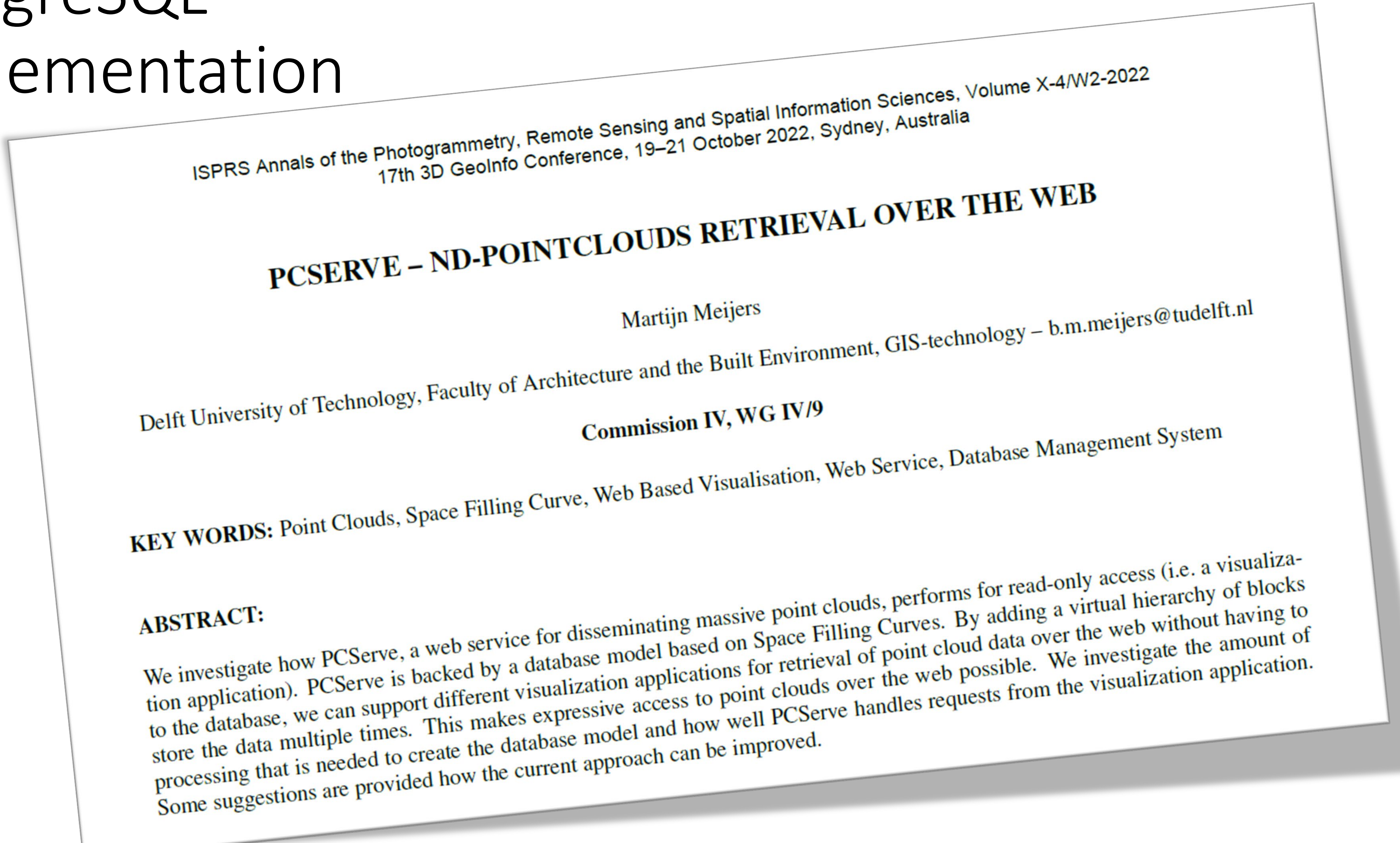
$$F(l,n) = \frac{2^{(n-1)l}-1}{2^{(n-1)(L+1)}-1}$$

for l between 0 and $L+1$
and n number of dimensions

- using random generator U (uniform between 0 and 1) to generate level l **(cLoI)** (between 0 and $L+1$) for next point in nD space:

$$l = \frac{\ln((2^{(n-1)(L+1)}-1)U+1)}{(n-1)\ln 2}$$

PostgreSQL Implementation



ISPRS Annals of the Photogrammetry, Remote Sensing and Spatial Information Sciences, Volume X-4/W2-2022
17th 3D GeoInfo Conference, 19–21 October 2022, Sydney, Australia

PCSERVE – ND-POINTCLOUDS RETRIEVAL OVER THE WEB

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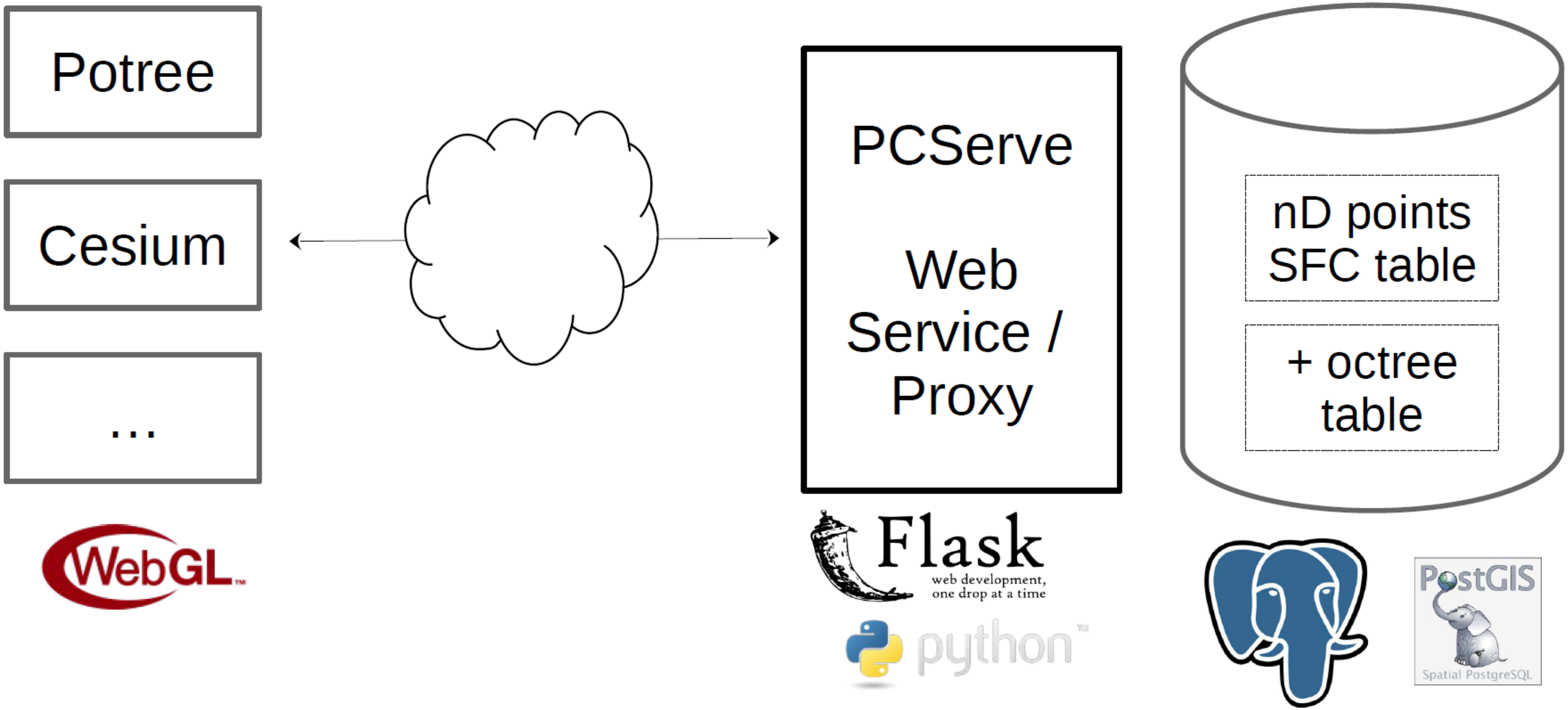
Commission IV, WG IV/9

KEY WORDS: Point Clouds, Space Filling Curve, Web Based Visualisation, Web Service, Database Management System

ABSTRACT:

We investigate how PCServe, a web service for disseminating massive point clouds, performs for read-only access (i.e. a visualization application). PCServe is backed by a database model based on Space Filling Curves. By adding a virtual hierarchy of blocks to the database, we can support different visualization applications for retrieval of point cloud data over the web without having to store the data multiple times. This makes expressive access to point clouds over the web possible. We investigate the amount of processing that is needed to create the database model and how well PCServe handles requests from the visualization application. Some suggestions are provided how the current approach can be improved.

Implementation: PCServe



nD Convex polytope query

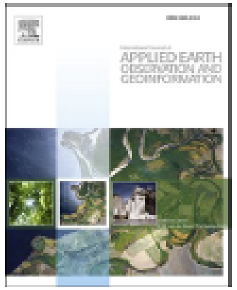
International Journal of Applied Earth Observations and Geoinformation 105 (2021) 102625

ELSEVIER

Contents lists available at ScienceDirect

International Journal of Applied Earth Observations and Geoinformation

journal homepage: www.elsevier.com/locate/jag



Executing convex polytope queries on nD point clouds

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A R T I C L E I N F O

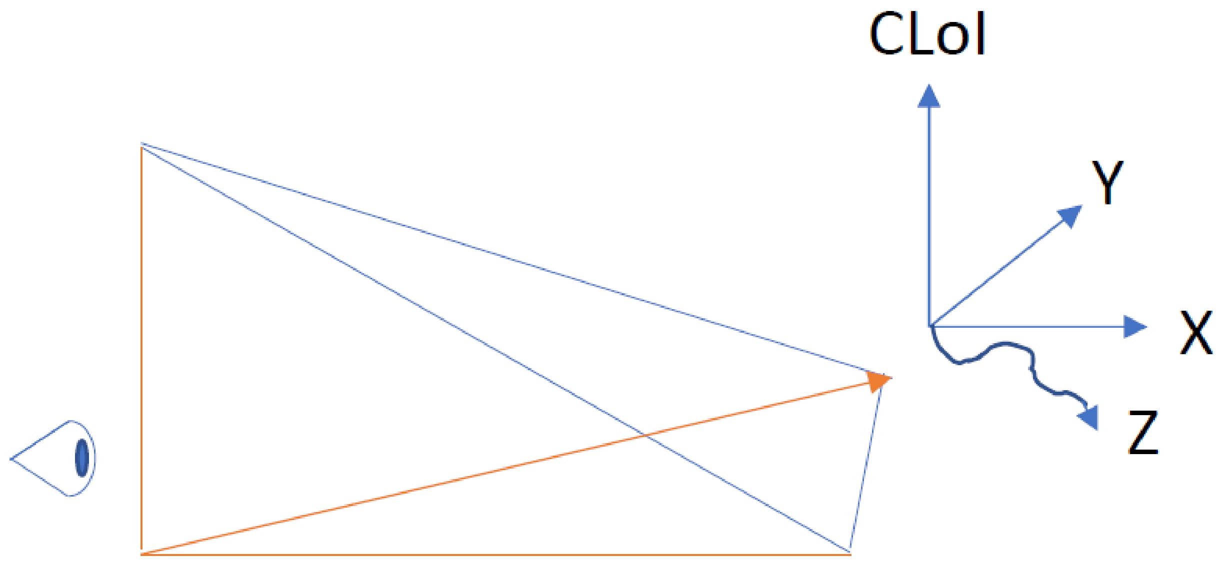
Keywords:
nD point clouds
Polytope query
Spatial data structures
CPLEX
Perspective view selection

A B S T R A C T

Efficient spatial queries are frequently needed to extract useful information from massive nD point clouds. Most previous studies focus on developing solutions for orthogonal window queries, while rarely considering the polytope query. The latter query, which includes the widely adopted polygonal query in 2D, also plays a critical role in many nD spatial applications such as the perspective view selection. Aiming for an nD solution, this paper first formulates a convex nD-polytope for querying. Then, the paper integrates three approximate geometric algorithms – SWEEP, SPHERE, VERTEX, and a linear programming method CPLEX, developing a solution based

nD query by convex polytopes

- convex polytope is more selective than a hyper-rectangle/sphere
- well defined in nD, based on half-space intersection
- fast implementation based on SFC/virtual 2^n-tree
- example view frustum selection



4D View Frustum with CLoI
(only drawn in 3D)

Apache Parquet (as alternative store)

- columnar store format, for serialized data (disk storage)
- structured (+ nested) data, compressed
- has a main memory cousin (uncompressed columnar)
  - Apache Arrow → Data frame libraries can read Parquet from disk into Arrow(2D, heterogeneous tabular data)
- you can interact via SQL with the Parquet files using query engine (DuckDb, Apache Drill)

Some nD PC data (load similar to PostgreSQL)

SFC key **Attributes**

sfc_key blob	gps_time double	scan_angle float	intensity uint16	return_number uint8	number_of_returns uint8	classification uint8	scan_direction uint8	is_edge_of_flight_line uint8
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\x8ES\xC…	494147.3131107338	27.0	170	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFC\x04…	493868.6779278455	16.002	118	1	1	2	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFC\xCD…	494146.86342112836	27.0	22	1	1	2	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFC\xF9…	494146.83669732255	27.0	37	1	1	2	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFF,2\xF8	493869.0259201808	16.002	64	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFF\xCB…	494146.41376256285	28.002	30	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,N\xFF\xD7…	493868.97246252943	15.0	184	1	1	2	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,O\xF7X\x0…	493870.1446405349	16.002	230	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x0E\x8C…	493870.0054991533	15.0	66	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x0E\xA0…	493870.1339485246	16.002	195	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x0E\xBB…	493870.0858279384	15.0	48	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x0F;\xF1&	493870.03758022806	16.002	200	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x10o\x8A}	493869.855603322	16.002	47	1	1	6	1	0
\x00\x00\x00\x00\x10\x02~\x8C\xC3,P\x10r\x93=	493869.74327855057	13.998	200	1	1	2	1	0
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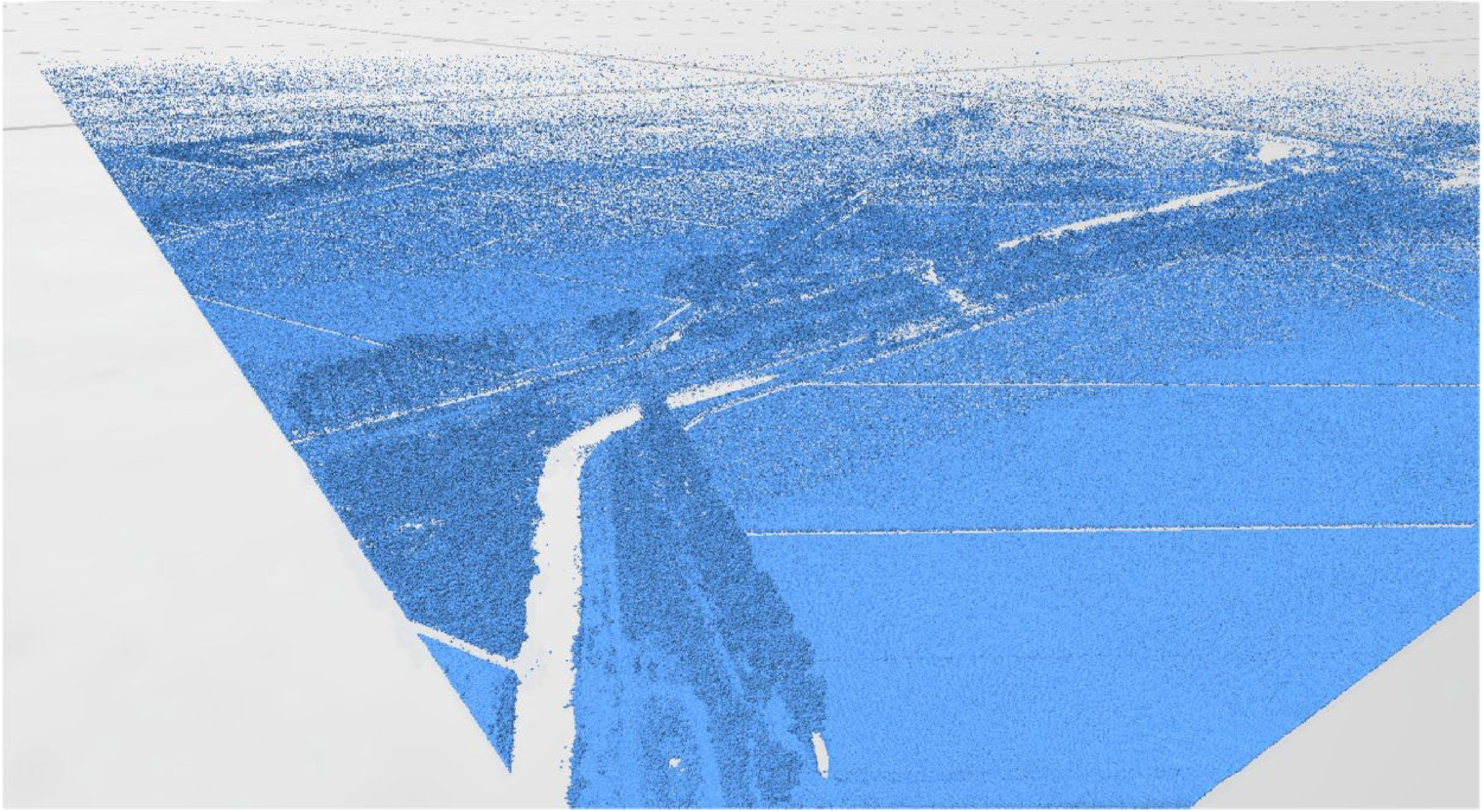
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7ws…	164798893.0589545	-10.002	171	1	1	2	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wt…	164798893.02829105	-10.002	16	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wt…	164798893.07124695	-10.002	39	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wt…	164798893.0466985	-10.002	129	1	1	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wu…	164798892.99145013	-10.002	49	2	2	2	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wupz	164798892.9668992	-10.002	60	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wu…	164798892.96690187	-10.002	18	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wu…	164798892.9668992	-10.002	133	2	2	2	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wu…	164798892.98529118	-9.0	95	1	3	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wv…	164798892.99755764	-9.0	164	2	2	2	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7wvy(	164798892.99755764	-9.0	43	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7ww3M	164798893.0466725	-9.0	23	1	2	1	1	0
\x00\x00\x00\x00\x10\x02~\x9F\xFF\xEB\xD7ww7g	164798893.0589441	-9.0	155	1	1	2	1	0

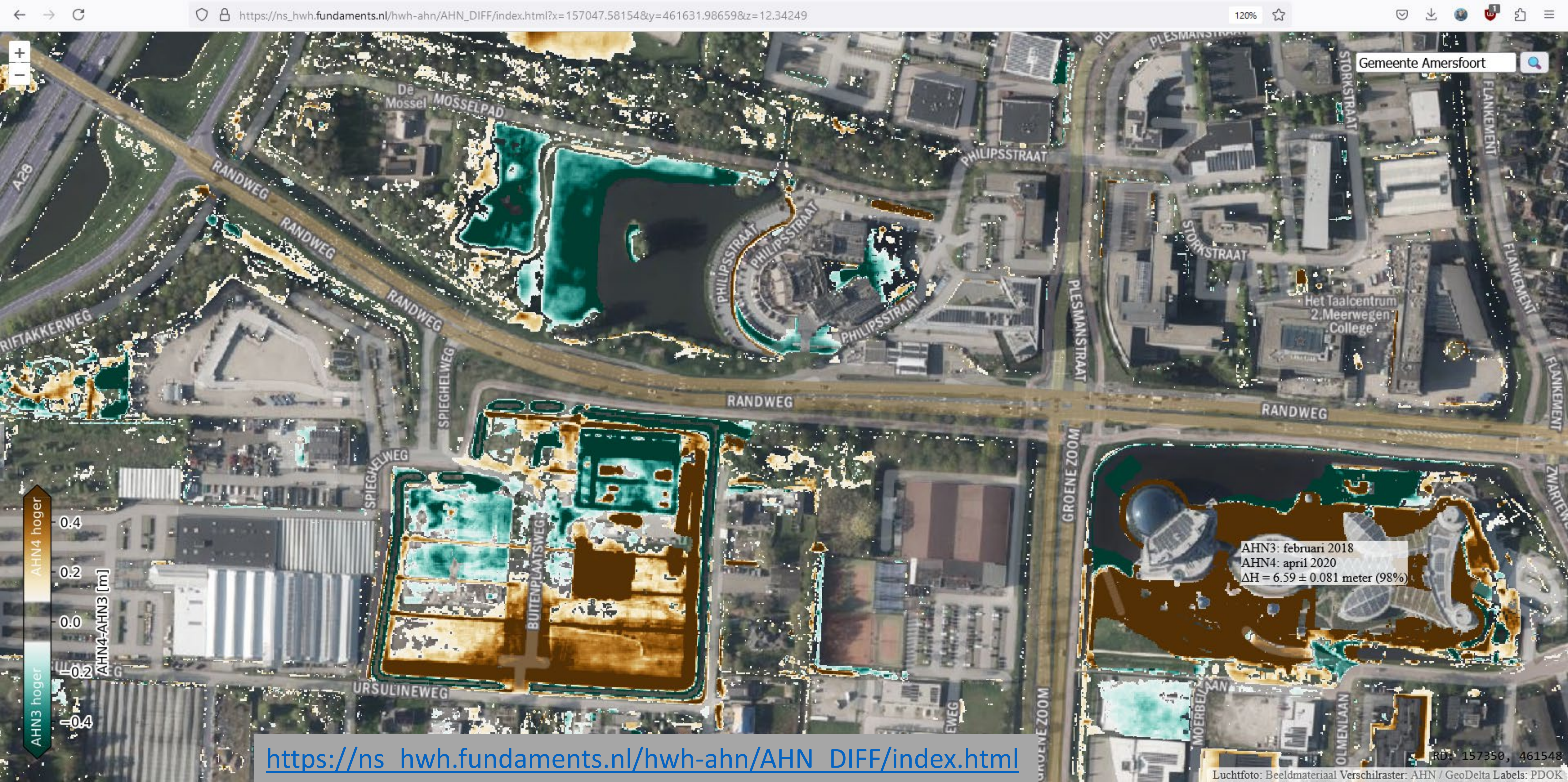
6083217 rows (40 shown) 9 columns

Row groups + **Columns** = Column Chunks

Integrated Space / cLoI query



Raster based change detection



https://ns_hwh.fundaments.nl/hwh-ahn/AHN_DIFF/index.html

Fine, but...

- grid is less detailed than PC
- grid can only be displayed in 2D
- grid needs to be computed first

- much better to have direct point cloud change detection

Comparison of Cloud-to-Cloud Distance Calculation Methods - Is the Most Complex Always the Most Suitable?

Vitali Diaz, Peter van Oosterom, Martijn Meijers, Edward Verbree, Nauman Ahmed, and Thijs van Lankveld

Abstract Cloud-to-cloud (C2C) distance calculations are frequently performed as an initial stage in change detection and spatiotemporal analysis with point clouds. There are various methods for calculating C2C distance, also called inter-point distance, which refers to the distance between two corresponding point clouds captured at different epochs. These methods can be classified from simple to complex, with more steps and calculations required for the latter. Generally, it is assumed that a more complex method will result in a more precise calculation of inter-point distance, but this assumption is rarely evaluated. This paper compares eight commonly used methods for calculating the inter-point distance. The results indicate that the accuracy of distance calculations depends on the chosen method and a characteristic related to the point density, the intra-point distance, which refers to the distance between points within the same point cloud. The results are helpful for applications that analyze spatiotemporal point clouds for change detection. The findings will be helpful in future applications, including analyzing spatiotemporal point clouds for change detection.

Keywords Cloud-to-cloud distance calculation · Change detection · Spatiotemporal analysis

This article was selected based on the results of a double-blind review of an extended abstract

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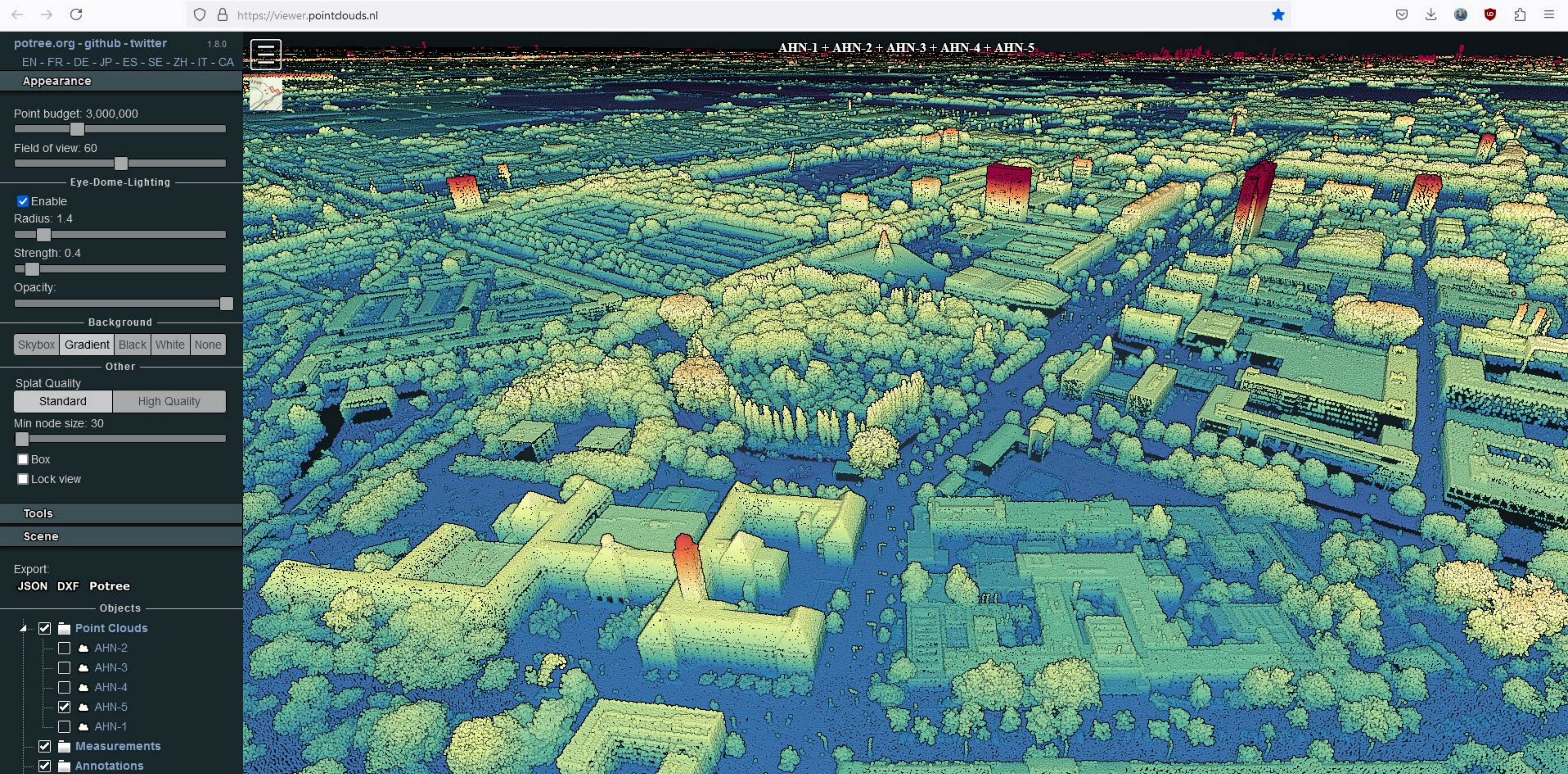
T. H. Kolbe et al. (eds.), *Recent Advances in 3D Geoinformation Science*, Lecture Notes in Geoinformation and Cartography, https://doi.org/10.1007/978-3-031-43699-4_20

SFC-based ultra-fast change detection

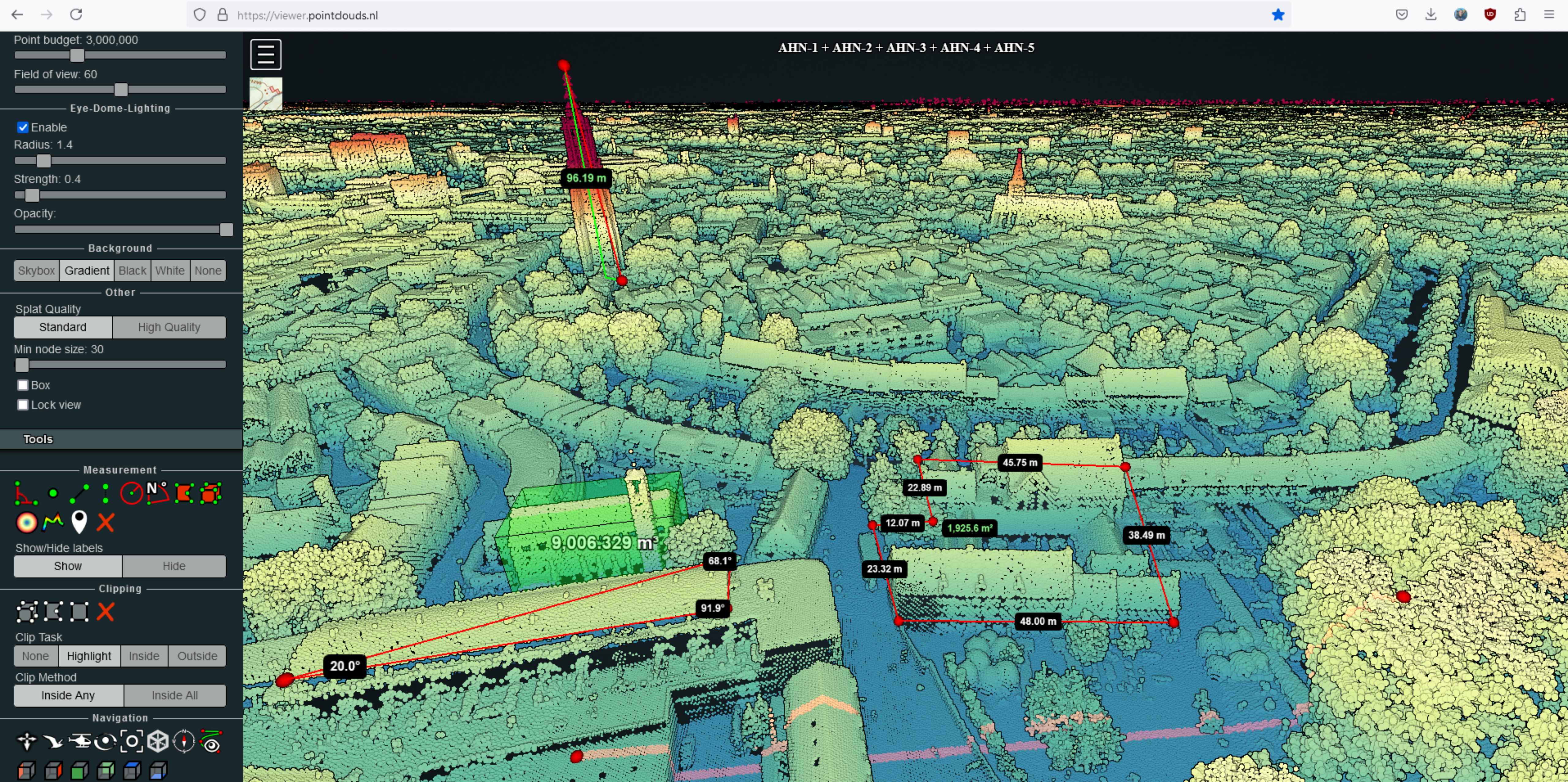
- per epoch, preparation of PC data set
    1. scaling and offsetting (SFC always in a cube)
    2. SFC key calculation
    3. sorting SFC key column

- batch process NN distance calculation (advanced merge join 2 epochs): for every point P in epoch 2:
    1. search the previous and next SFC key of the calculated SFC key in epoch 1
    2. decode and unscale these two SFC keys (previous and next)
    3. find approximate nearest neighbor (NN) of the 2 candidates
       (option: box query in epoch 1 with P as center and distance P-NN as radius)
    4. output d and dx,dy,dz

http://viewer.pointclouds.nl all AHN versions in potree



Various tools: height, area, volume, angles, profile,..



potree conversion on ronna

name	#points	#files in	Input size (Gb)	Output size (Gb)	Duration (hours)
AHN1	11.984.853.767	1358	33,1	44,2	0,17
AHN3	557.925.797.136	1374	2390,7	5035,8	12,29
AHN4	947.364.043.509	1381	6145,4	9931,8	33,38
AHN5 part	289.944.615.278	499	1394,3	2695,9	8,59

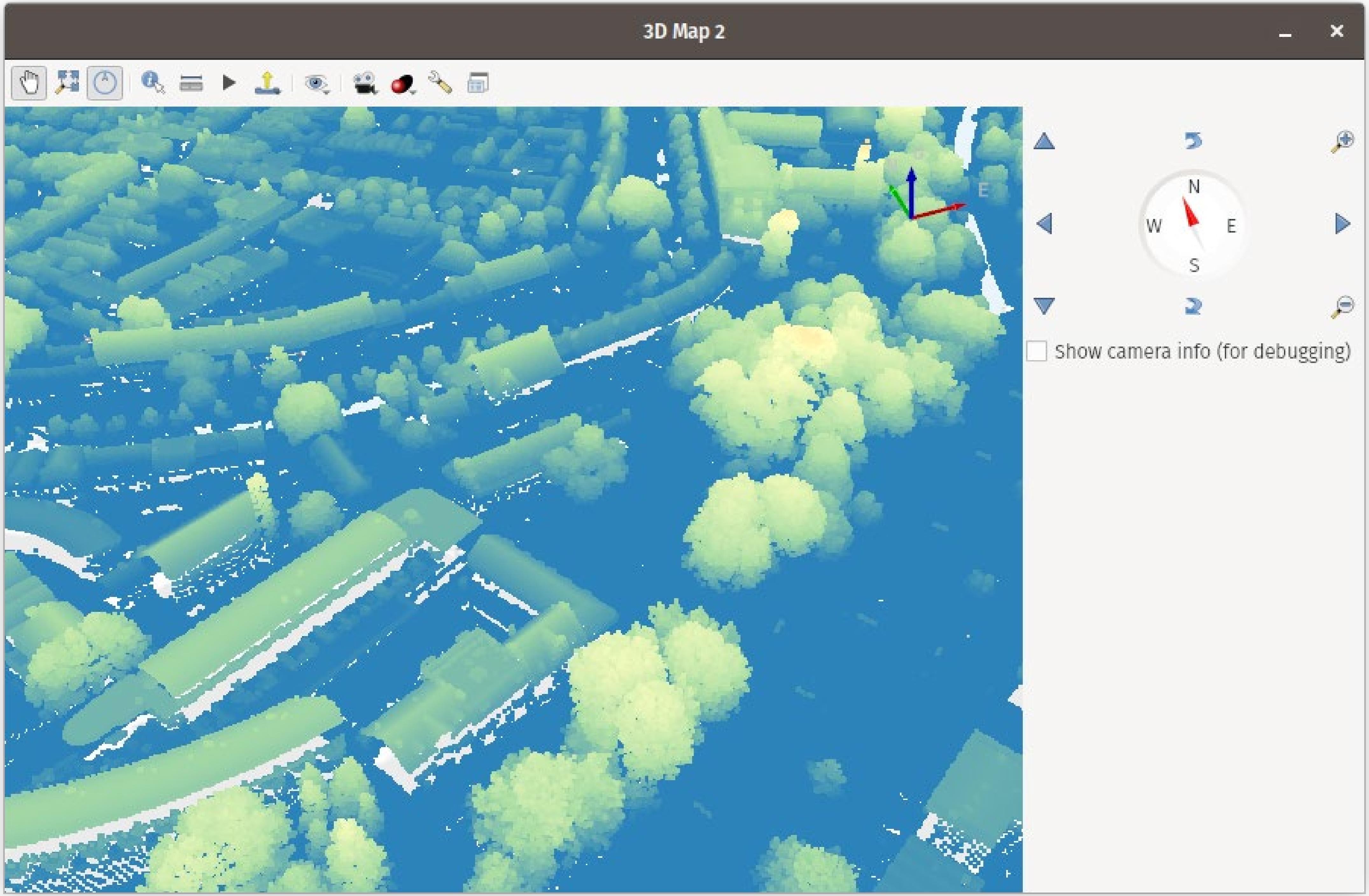
AHN2 converted before (previous project)
Duration conversion on ronna, multi-user

Virtual Point Clouds and Cloud Optimized Point Cloud

- Virtual Point Cloud (VPC) file = SpatioTemporal Asset Catalogs (STAC)
- extension on top of GeoJSON with PC metadat
- contains links to COPC .laz files (or EPT, Entwine Point Tile)

- Cloud Optimized Point Cloud (COPC) file = data
- COPC is .laz which has embedded Octree
- specs on https://copc.io/ (by Hobu, Inc.)

- load VPC in **QGIS** as a single point cloud layer
  (rather than each file as a separate map layer)

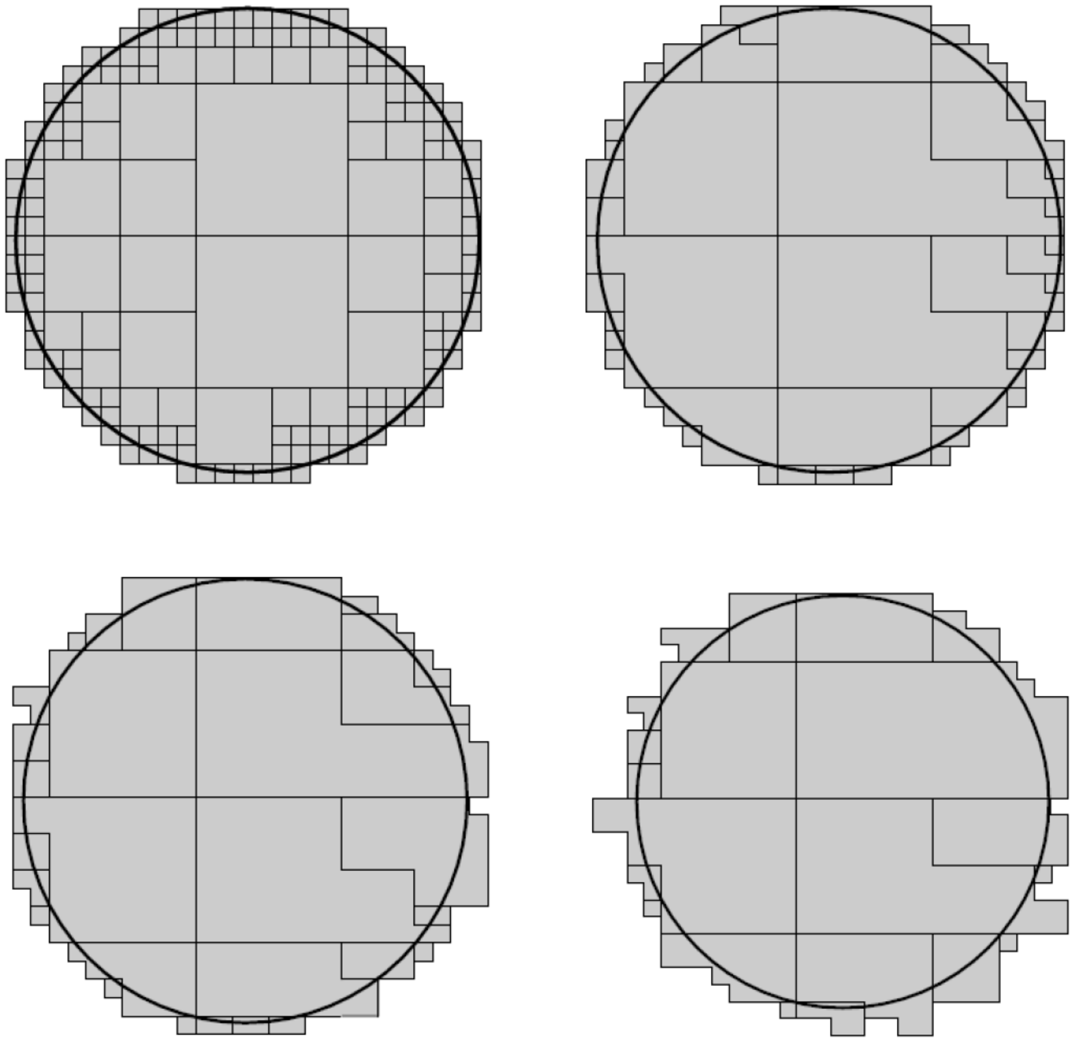


3D Map 2
N
W
E
S
E
Show camera info (for debugging)

Agenda

- nD-PointCloud recap
  - foundations
  - PostgreSQL implementation
  - nD Convex polytope query
  - Apache Parquet
  - change detection
  - AHN potree conversions
  - VPC/COPC

- **conclusion**
  - **future work**
  - **main publications**



Conclusion

- designed and tested nD-PC organization (with cLoI) in resp. DBMS and files, and good results obtained
- explored and cleaned spatio-temporal point cloud data, and analyzed in detail the possible change detection options → NN preferred
- Virtual Point Clouds/Cloud Optimized Point Cloud and potree conversions AHN
- quality of point cloud-based change detection and fast implementation
- current practice tools not yet cLoI-aware and space first (not time)
- active at various meetings (OGC, 3D GeoInfo, FOSS4G, EGU) and publications
- Geomatics/GIMA students doing (thesis) projects with point clouds

Future work (1/2)

- our students
- new projects (e.g. POINT-TWIN)
- complete publications

Future work (2/2)

- cLoI aware viewers and other clients (computations),
  using selection with flat hyperplanes (convex polytope)
- standardization of format and protocols (binary Parquet files)
- on-the-fly CRS transformations of selections, or pre-computing of whole data sets (on HPC/HTC)
- explore cLoI to integrate datasets from different scales (after geo-referencing/CRS transformation)
- nationwide AHN change detection (buildings, vegetation, ..) by
  - adding 1 just or all 3 directions
  - store result integrated (dimension of attribute) or separate from points
  - interactive of massive preprocessing (on HPC/HTC), but fast use
  - backward of forward changes
  - for CoastScan, option to skip epochs (hours, days, weeks, months)

Publications (1/2)

- Vitali Diaz, Peter van Oosterom, Martijn Meijers, Edward Verbree, Nauman Ahmed, Thijs van Lankveld, Comparison of Cloud-to-Cloud Distance Calculation Methods - Is the Most Complex Always the Most Suitable?, Chapter in: Recent Advances in 3D Geoinformation Science, Lecture Notes in Geoinformation and Cartography, Springer Nature Switzerland, pp. 229-334, 2024.
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- Zhenyu Liu, Peter van Oosterom, Jesús Balado, Arjen Swart, Bart Beers, Data frame aware optimized Octomap-based dynamic object detection and removal in Mobile Laser Scanning data, In: Alexandria Engineering Journal, 74, pp. 327-344, 2023.
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Publications (2/2)

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- Guan-Ting Zhang, Edward Verbree, Xiao-Jun Wang, An Approach to Map Visibility in the Built Environment From Airborne LiDAR Point Clouds, In: IEEE Access, Institute of Electrical and Electronics Engineers (IEEE), 9, pp. 44150-44161, 2021.
- H. Liu, P. Van Oosterom, B. Mao, M. Meijers, R. Thompson, An efficient nD-Point Data Structure for Querying Flood Risks, Chapter in: The International Archives of the Photogrammetry, Remote Sensing and Spatial Information Sciences, Copernicus GmbH, XLIII-B4-2021, pp. 367-374, 2021.

Thanks
for your
attention!
Questions?