ABSTRACT

Method for encoding and decoding attributes of a point cloud. Therein, the encoding method comprises: determining a true transform coefficient by applying RAHT to the attributes of a present node; determining a difference between the attributes of a present parent node and each of the parent nodes in a first set of parent nodes sharing a face or an edge with the present node; selecting a second set from the first set of parent nodes according to the difference; determining a predicted value for the attributes of the present node according to the attributes of the second set of parent nodes; determining a predicted transform coefficient by applying RAHT to the predicted value of the attributes of the present node; determining a residual from the true transform coefficient and the predicted transform coefficient; encoding the residual to produce encoded data of attributes of the point cloud for the bitstream.

Fig. 1