ABSTRACT

A method and apparatus of encoding and decoding point cloud geometry data sensed by at least one sensor associated with a sensor index, the point cloud geometry data being represented by ordered coarse points occupying some discrete positions of a set of discrete positions of a two-dimensional space. The method comprises selecting, for a first occupied coarse point having a first sensor index and being associated with a first radius, a selected predicting radius from at least one second radius associated with at least one second occupied coarse point and from at least one third radius associated with at least one third occupied coarse point; - encoding, in the bitstream, a data indicating if the selected predicting radius is equal to either a second radius or a third radius; and predictive encoding, in the bitstream, a residual radius between the first radius and the selected predicting radius.

Fig. 17