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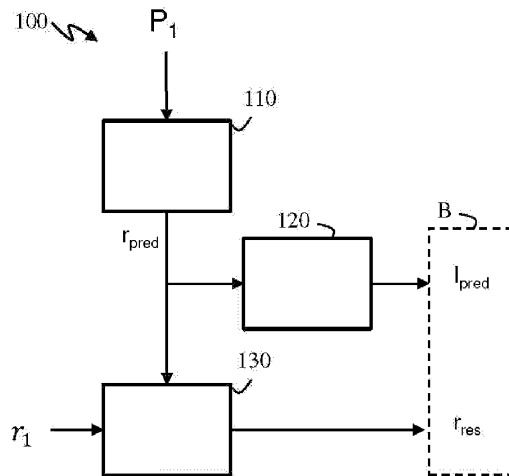


Fig. 17

(57) Abstract: There is provided methods and apparatus of encoding/decoding point cloud geometry data sensed by at least one sensor associated with a sensor index, said 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 (110), for a first occupied coarse point (P_1) having a first sensor index (λ_1) and being associated with a first radius (r_1), a selected predicting radius (r_{pred}) from at least one second radius (r_2) associated with at least one second occupied coarse point (P_2) and from at least one third radius (r_3) associated with at least one third occupied coarse point (P_3); and -encoding (120), in the bitstream, a data (l_{pred}) indicating if the selected predicting radius (r_{pred}) is equal to either a second radius (r_2) or a third radius (r_3).

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