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(71) **Applicant: BEIJING XIAOMI MOBILE SOFTWARE CO., LTD.** [CN/CN]; No. 018, Floor 8, Building 6, Yard 33, Middle Xierqi Road, Haidian District, Beijing 100085 (CN).

(72) **Inventors: LASSERRE, Sebastien;** No. 018, Floor 8, Building 6, Yard 33, Middle Xierqi Road, Haidian District, Beijing 100085 (CN). **TAQUET, Jonathan;** No. 018, Floor 8, Building 6, Yard 33, Middle Xierqi Road, Haidian District, Beijing 100085 (CN).

(74) **Agent: TSINGYIHUA INTELLECTUAL PROPERTY LLC;** Room 201, 2nd Floor, Building 1, No. 45, Beiwa Road, Haidian District, Beijing 100142 (CN).

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(54) Title: METHOD AND APPARATUS OF ENCODING/DECODING POINT CLOUD GEOMETRY DATA SENSED BY AT LEAST ONE SENSOR

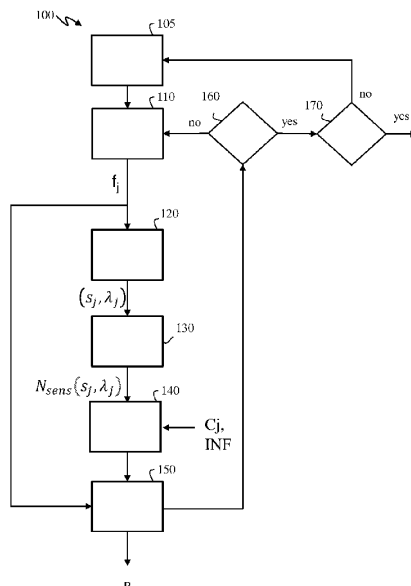


Fig. 13

(57) Abstract: Provided are methods and apparatus of encoding/decoding point cloud geometry data represented by ordered coarse points occupying some discrete positions of a set of discrete positions of a two-dimensional space. The encoding method comprises obtaining (105) at least one binary data (f_j) representative of an order index difference representative of a difference between order indices of two consecutive occupied coarse points and encoding each of said at least one binary data (f_j) by: -obtaining (120) coordinates (s_j, λ_j) of a current coarse point (P_j) within the two-dimensional space; -obtaining (130) a sensing number ($N_{\text{sens}}(s_j, \lambda_j)$) from the current coarse point (P_j), said sensing number ($N_{\text{sens}}(s_j, \lambda_j)$) being representative of an average number of consecutive sensing needed by a sensor (λ_j) associated with the current coarse point (P_j) to sense another coarse point; and -entropy encoding (150), into the bitstream, the binary data (f_j) based on the sensing number ($N_{\text{sens}}(s_j, \lambda_j)$).

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