



# Workshop on Coding Technologies for Immersive Audio/Visual Experiences

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# Immersive Experiences

- **Immersion** can be
  - defined as the **state of consciousness** where a *visitor* or *immersant's* awareness of physical self is **transformed** by being surrounded in an artificial **environment**.
- An **immersive digital environment**
  - [artificial](#), [interactive](#), computer-created [scene](#) or "world" within which users can immerse themselves.

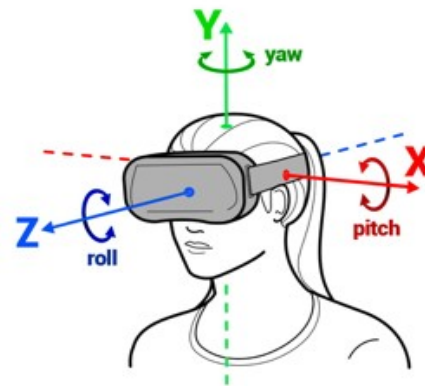


# Immersive Experiences

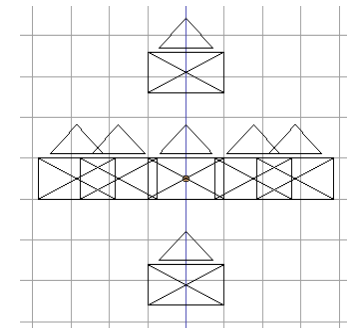
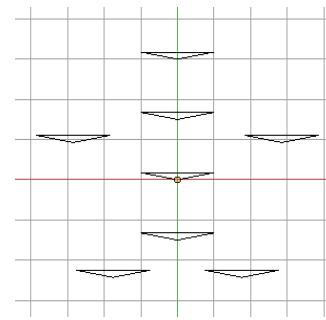
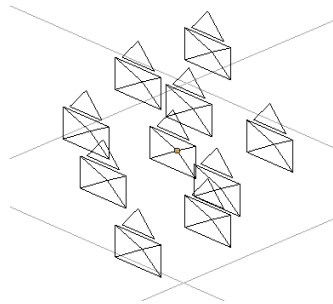
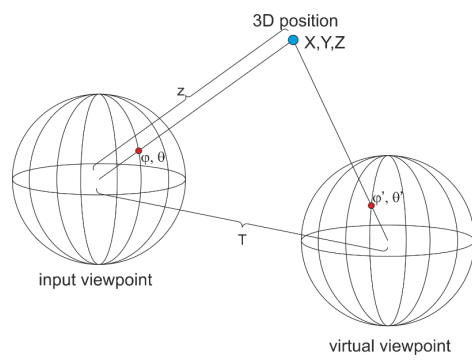
- **Immersion** can also be
  - used for describing partial or complete **suspension of disbelief** by enabling action or reaction to stimulations encountered in a virtual or artistic environment.
  - The greater the suspension of disbelief, the greater the degree of presence achieved.

# Immersive Experiences

- To create a sense of **full immersion**, the 5 senses (sight, sound, touch, smell, taste) must perceive the digital environment to be physically real.
- **Immersive technology** can **perceptually fool** the senses through:
  - Panoramic 3D displays (visual)
  - Surround sound acoustics (auditory)
  - Haptics and force feedback (tactile)
  - Smell replication (olfactory)
  - Taste replication (gustation)

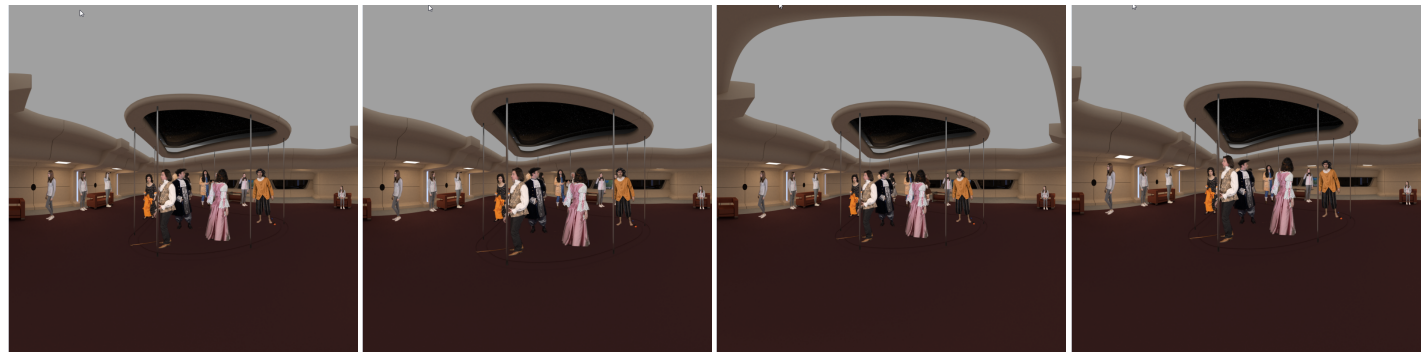


# Multi-Sphere for Parallax



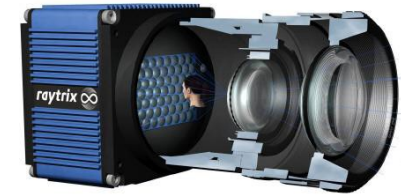
30cm radius

*TechnicolorHijack.*  
10 semi-ERP RGB+D virtual cameras

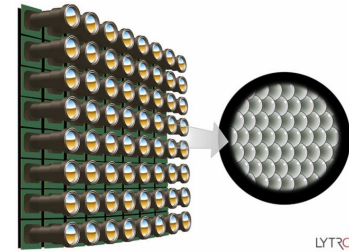


# Dense Light Fields

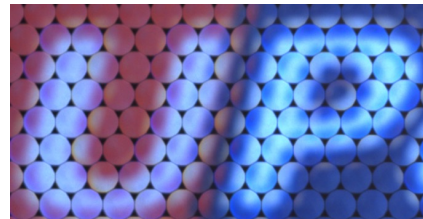
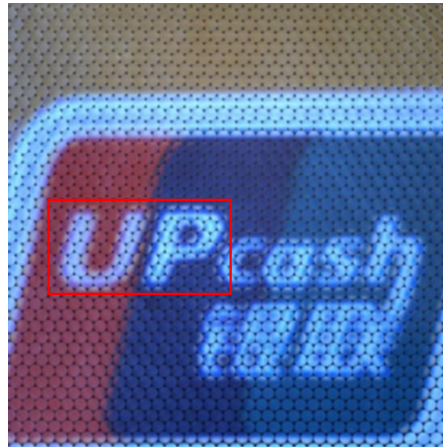
- Lenslet cameras



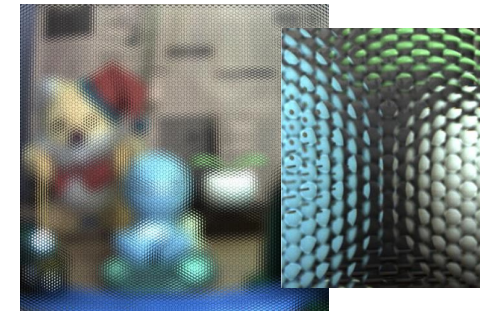
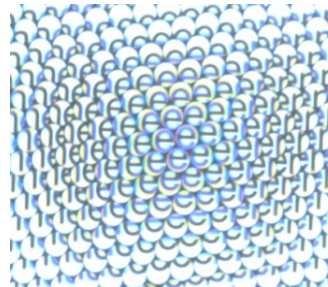
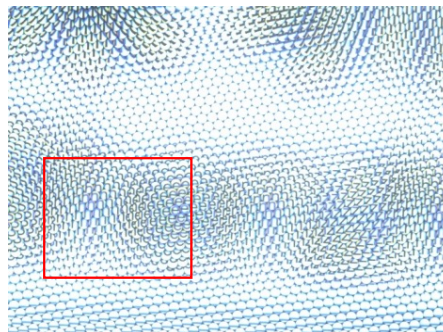
From multi-cams to micro-lenses



- Plenoptic 1.0



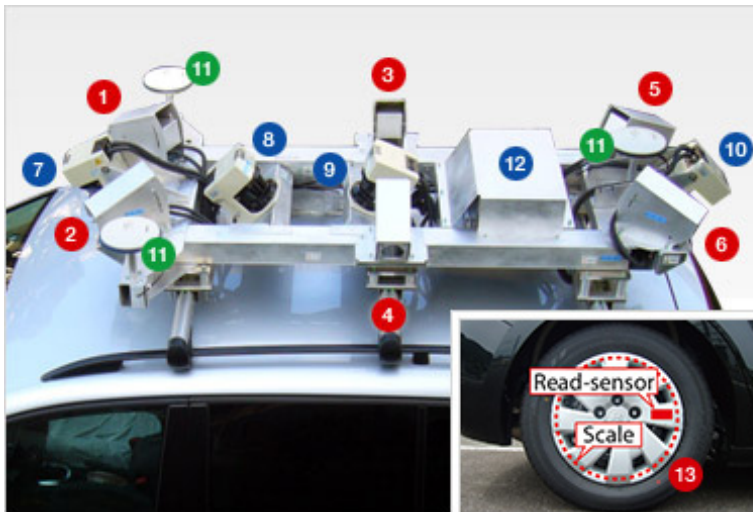
- Plenoptic 2.0



# Point Cloud Capturing



Example studio for capturing dynamic point clouds

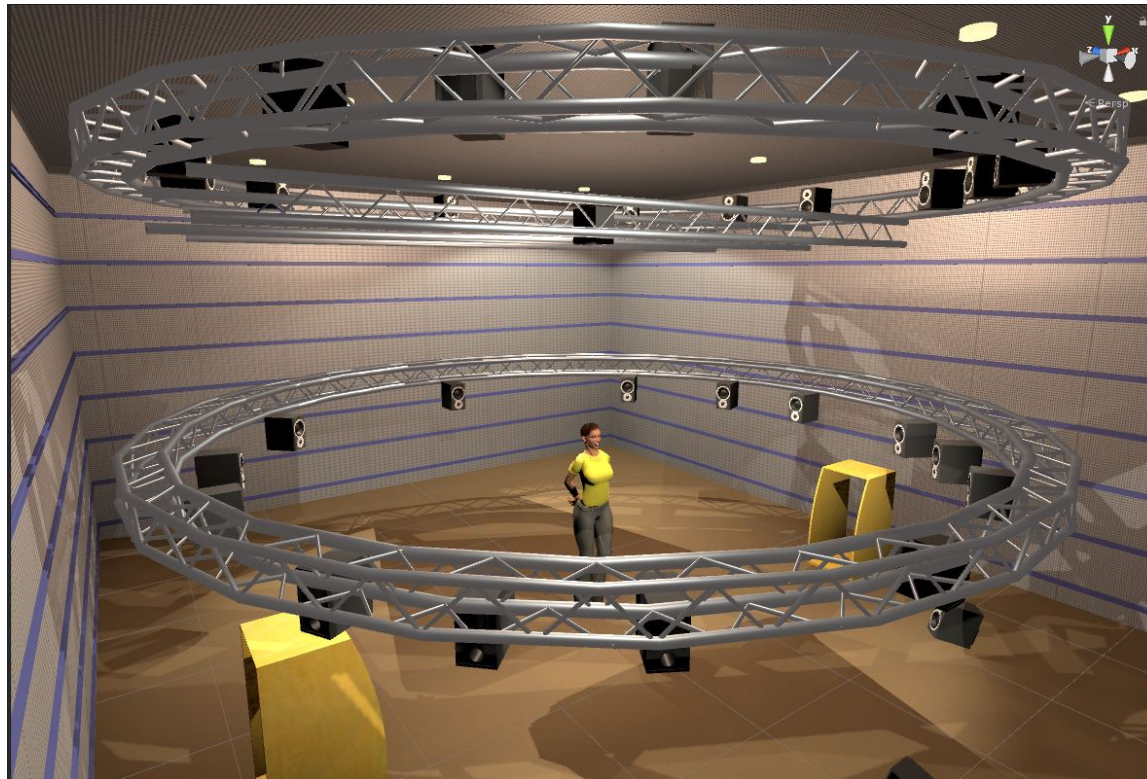


- 1 Camera(front;right)
- 2 Camera(front;left)
- 3 Camera(side;right)
- 4 Camera(side;left)
- 5 Camera(rear;right)
- 6 Camera(rear;left)
- 7 Laser scanner(front;downward)
- 8 Laser scanner(rear;upward)
- 9 Laser scanner(front;upward)
- 10 Laser scanner(rear;downward)
- 11 GPS antenna
- 12 IMU
- 13 In-wheel odometer

Sensor system for generating mobile mapping point clouds

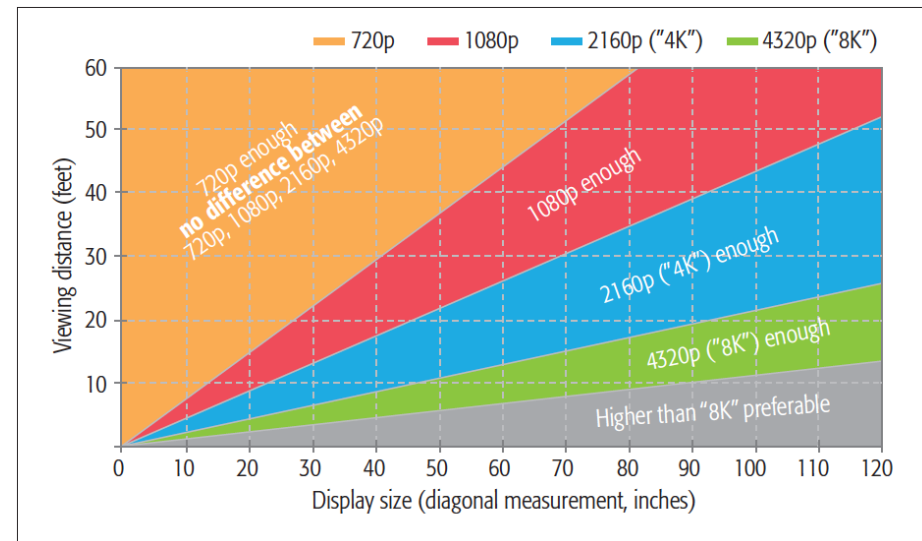
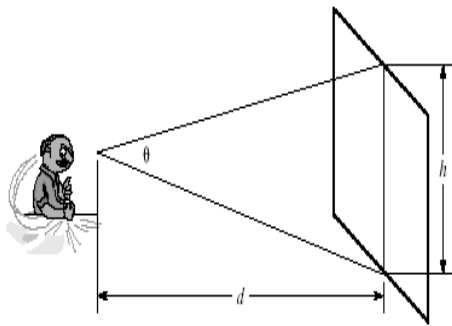


# Virtual Acoustic Environment

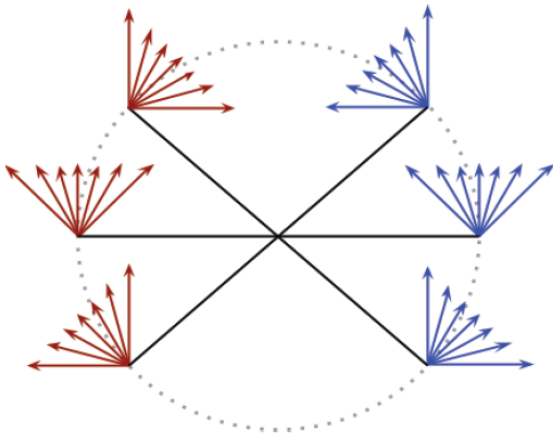
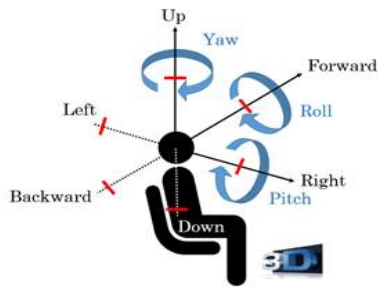


# Big Data – 3 Degree of Freedom

- Retina resolution at fovea:  $\sim 200$  PPD (pixel per degree)
- 4K UHD, 16:9, 3-times-height-of-picture viewing distance,
  - $36^\circ$  FoV  $\rightarrow \sim 100$  PPD
- 4K UHD,  $360^\circ$  omnidirectional video  $\rightarrow \sim 11$ PPD
  - ✓  $200\text{PPD}$  ,  $360^\circ * 180^\circ$  ,  $72\text{K} * 36\text{K} \rightarrow 2.5\text{G pixel} \rightarrow 4,500\text{Gbps}$



# Big Data – 3 Degree of Freedom +





# Synthesis Results



Synthesis from 24 views

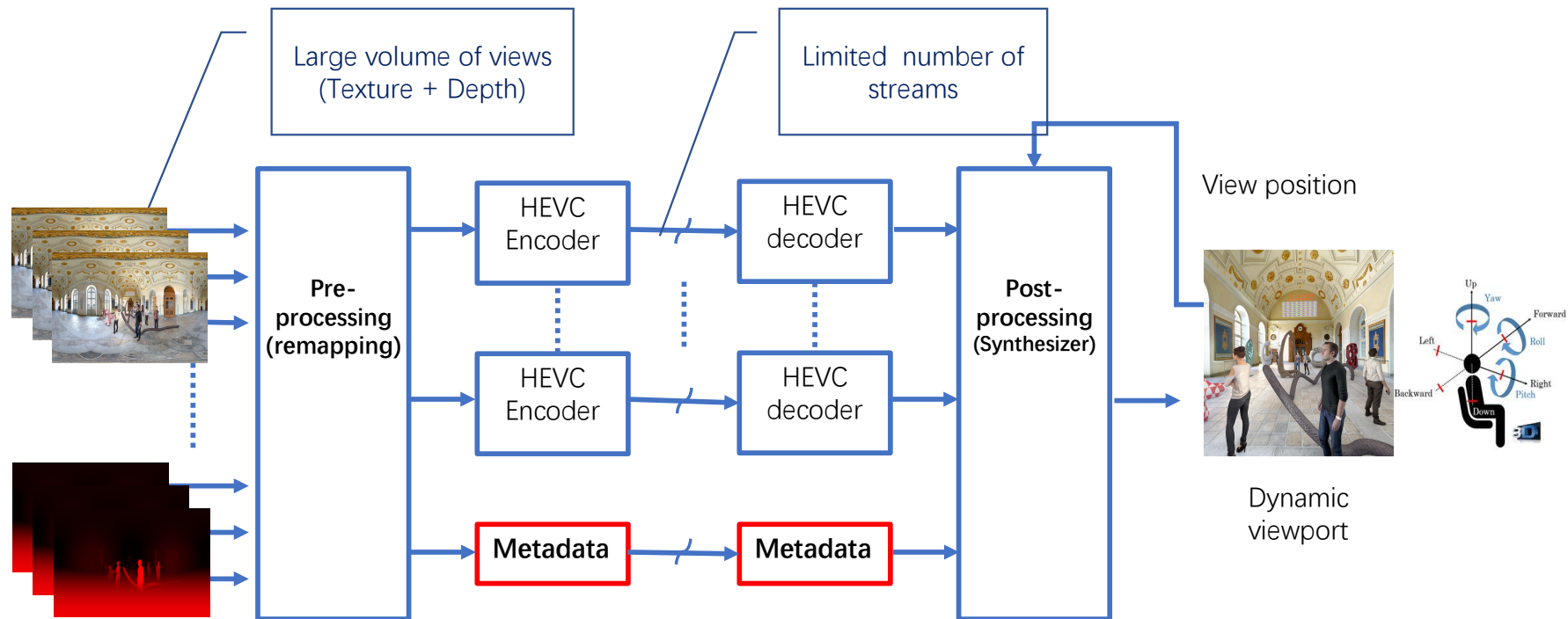


Synthesis from 8 views



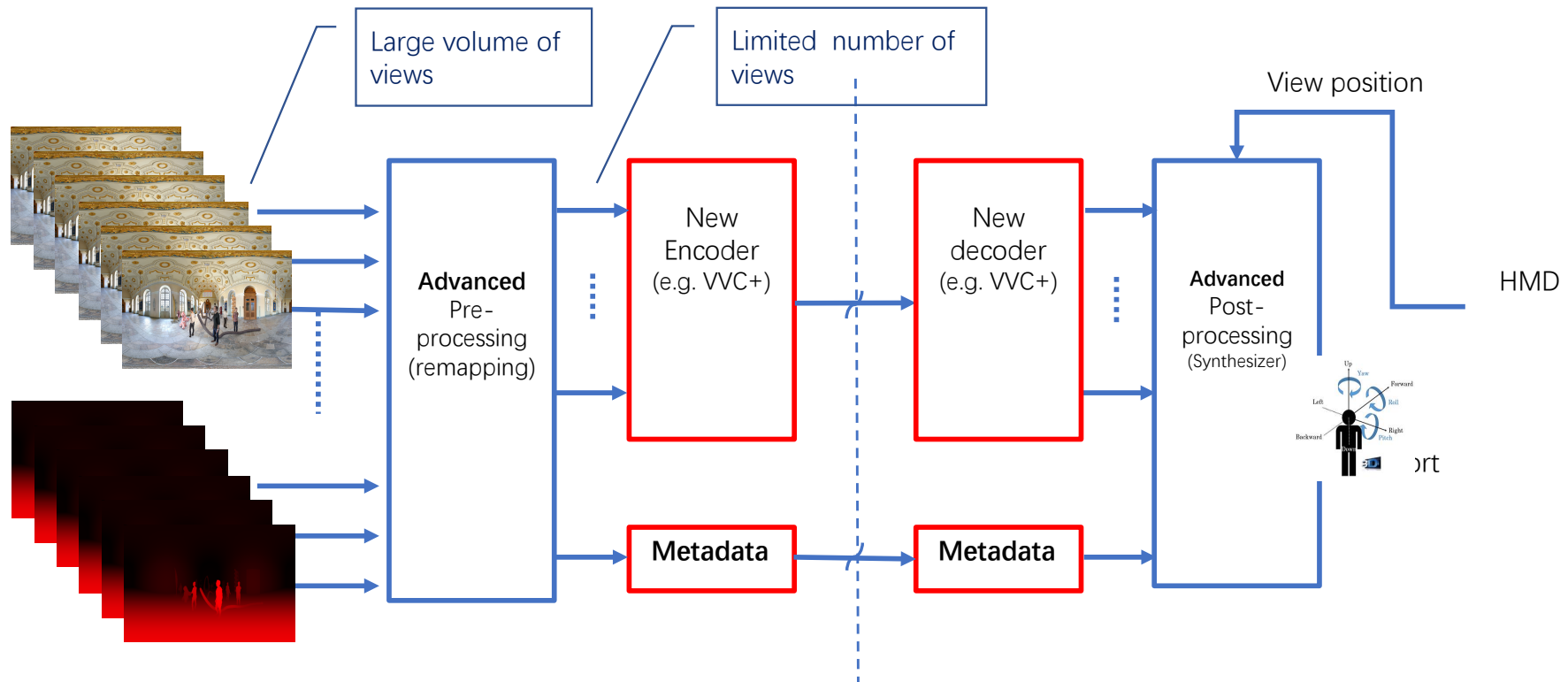
Synthesis from 2 views

# MPEG-I Visual 3DoF+ Activities



**3DoF+:** 3DoF with additional limited translational movements (typically, head movements)

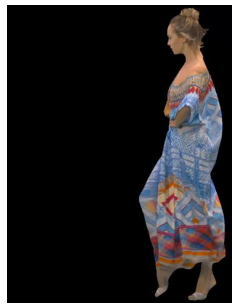
# MPEG-I Visual 6DoF Activities



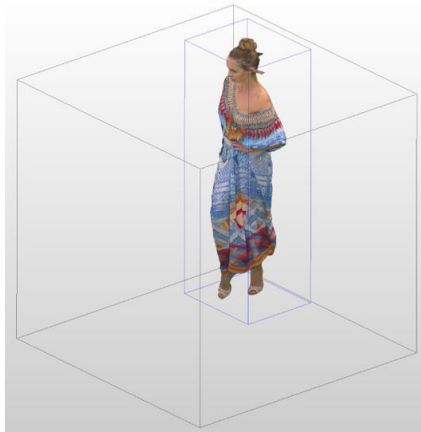
**6DoF:** 3DoF with full translational movements along X, Y and Z axes. A typical use case is a user freely walking through 3D 360 VR content



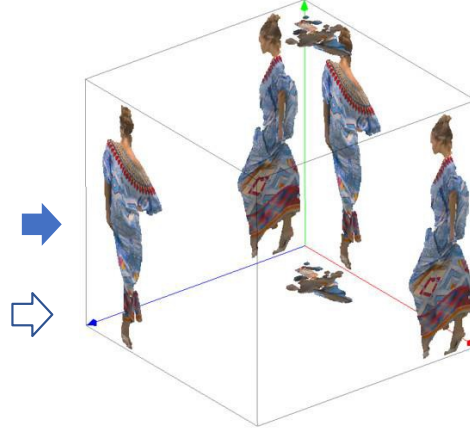
# Point Cloud Compression



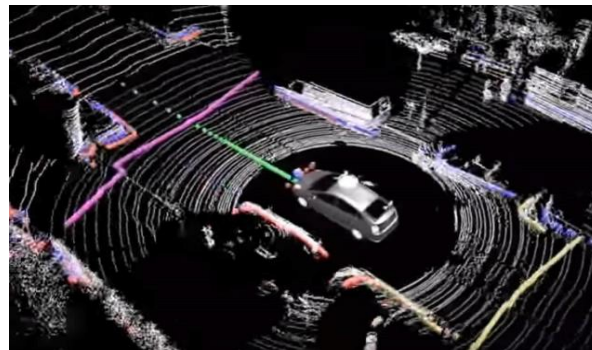
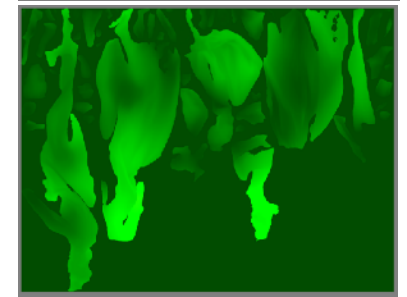
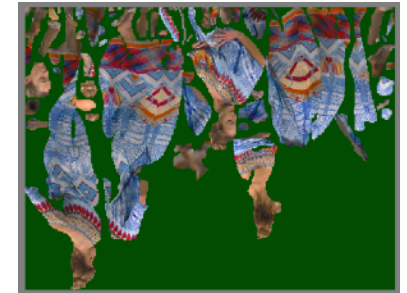
Animated  
Point Cloud  
(voxels)

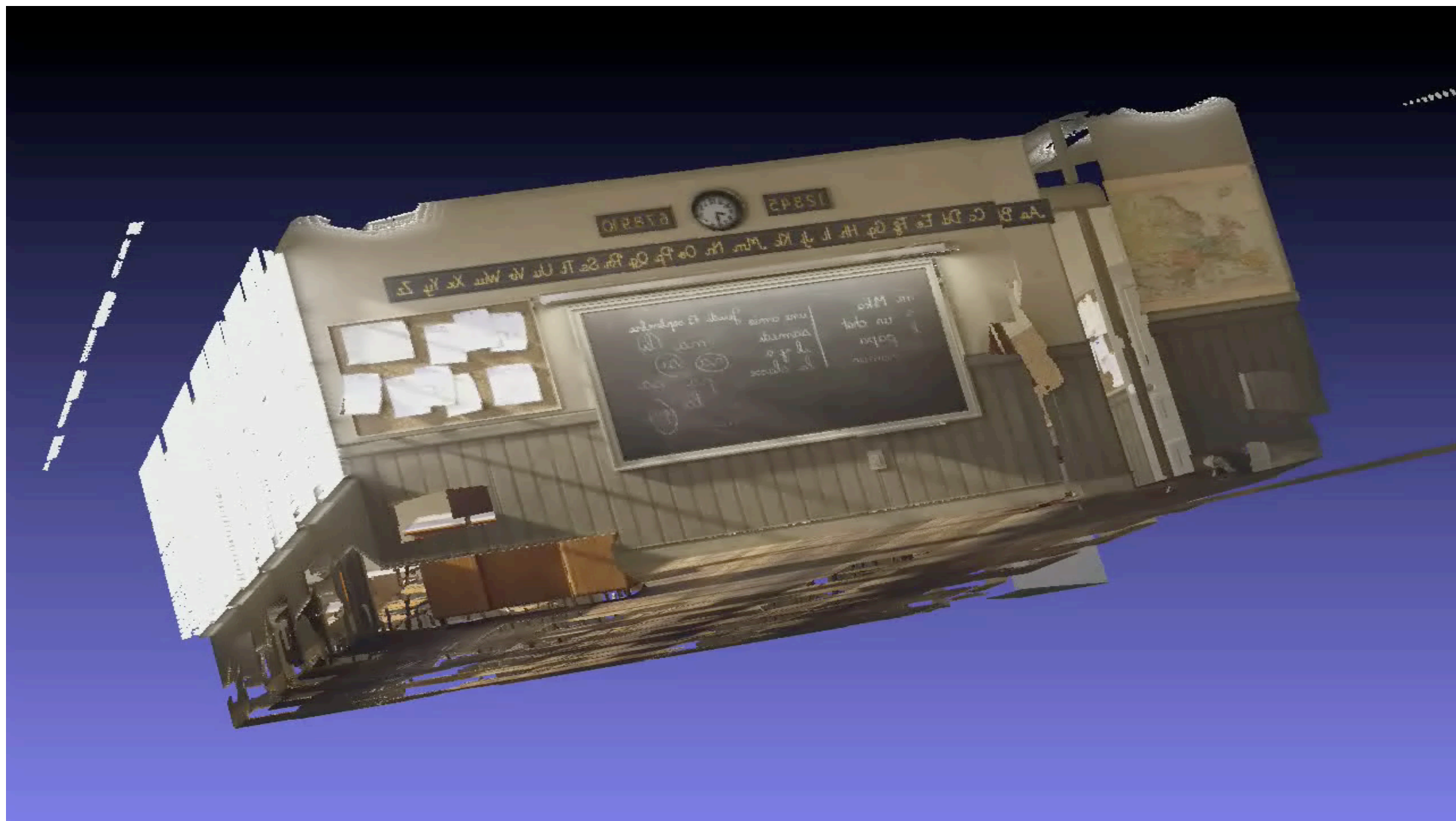


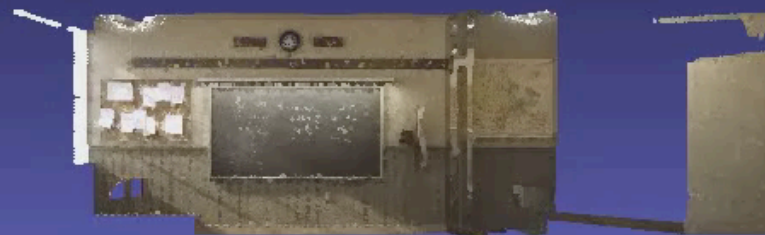
Bounding volume



Orthographic projection



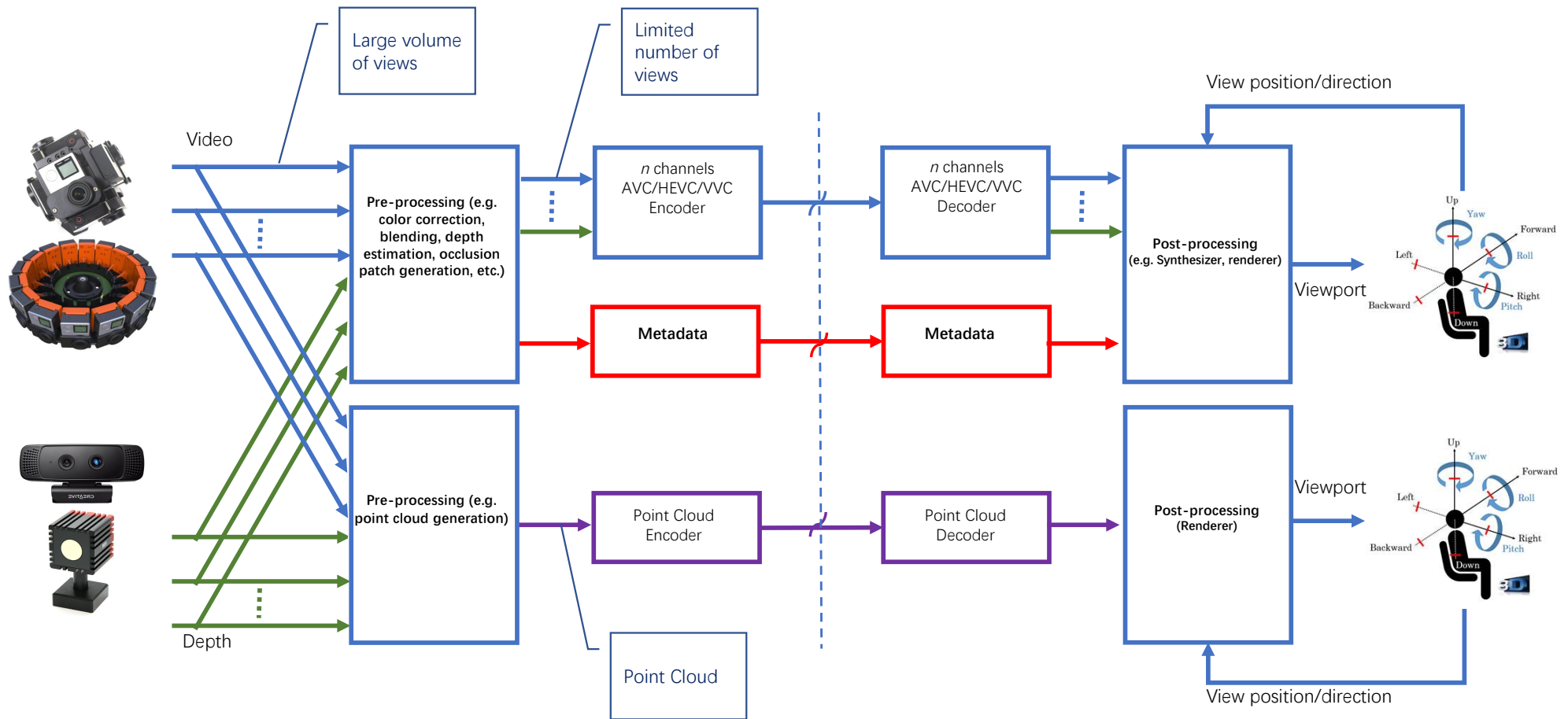




# # of Points

sequence	Frames	fps	# Pts	Geometry Precision
Queen	250	50	~1,000,000/fr	10 bit
8i VFB – Loot	300	30	~780,000/fr	10 bit
8i VFB – Red_and_Black	300	30	~700,000/fr	10 bit
8i VFB – Soldier	300	30	~1,500,000/fr	10 bit
8i VFB – Long_dress	300	30	~800,000/fr	10 bit
<b>classroomVideo</b>	<b>120</b>	<b>30</b>	<b>~120,000,000/fr</b>	<b>float</b>

# Video & Graphics based Workflow of Immersive Visual Content







Jan 2018

2019

2020

2021

2022

2023

Jan 2024

# Media Coding

Versatile Video Coding  
(360 degree)

6 DoF Audio

*Dense Representation of Light Field Video*

3DoF+ Video

*Video with 6 DoF*

Video Point Cloud Compression

*Point Cloud Compression v.2*

Geometry Point Cloud Compression

PCC Systems Support

Immersive Media Scene Description  
Interface

OMAF v.2

Immersive Media Metric

# Systems and Tools

Time slot	Topic	Speaker
1300-1315	Introduction	Lu Yu, Zhejiang University
1315-1345	Usecases and challenges about user immersive experiences	Valerie Allie, InterDigital
1345-1415	Overview of technologies for immersive visual experiences	Marek Domanski, Poznan University of Technology
1415-1445	MPEG-I Immersive Audio	Schuyler Quackenbush, Audio Research Labs
1445-1455	Brief introduction about demos: <ul style="list-style-type: none"> <li>▪ Integral photography display</li> <li>▪ Realtime interactive demo with 3DoF+ content</li> <li>▪ Plenoptic 2.0 video camera</li> <li>▪ A simple free-viewpoint television system</li> </ul>	<ul style="list-style-type: none"> <li>▪ NHK</li> <li>▪ InterDigital</li> <li>▪ Tsinghua University</li> <li>▪ Poznan University of Technology</li> </ul>
1455-1530	Demos Coffee break	
1530-1600	360° and 3DoF+ video	Bart Kroon, Philips
1600-1630	Point cloud compression	Marius Preda, Telecom SudParis, CNRS Samovar
1630-1700	How can we achieve 6DoF video compression?	Joel Jung, Orange
1700-1730	How can we achieve lenslet video compression?	Xin Jin, Tsinghua University, Mehrddad Teratani, Nagoya University