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**ISO/IEC JTC 1/SC 29/WG 11**

**CODING OF MOVING PICTURES AND AUDIO**

**ISO/IEC JTC 1/SC 29/WG 11 N19214**

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| **Source:** | **Video** |
| **Title:** | **Common Test Conditions for Immersive Video** |
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**Common Test Conditions for Immersive Video**

1. **Introduction**

Common test conditions are desirable to conduct coding experiments in a well-defined environment and ease the comparison of the outcome of experiments. This document specifies the common test conditions for immersive video activities. The common test conditions are defined to evaluate the coding efficiency, subjective quality, pixel rate and user experience of immersive video solutions. The technical approach is following these steps:

1. Compress test content,
2. Synthesize intermediate views from decoded views and metadata (when available),
3. Render viewports of real/virtual pose traces with a limited or a wider movement,
4. Evaluate coding efficiency and parallax effect, considering both decoded views and synthesized views.

The bitstream shall be viewer independent, meaning that neither the position nor the orientation of the viewer shall be considered when compressing the test content. The range of supported possible viewer positions is constrained and known.

Two different anchors are used: the first one, the “MIV anchor” (Metadata for Immersive Video), is HEVC + TMIV-based, and encodes atlases with the test model. The second one, the “MIV view anchor”, is also HEVC + TMIV based but directly encodes a subset of the source views.

1. **Test material**

This section describes the test material that is used in the common test conditions and defines the numbering of the views. References to input documents are included for a more detailed description of each sequence. Subsequent subsections provide download links for sequence data and metadata. CTC-specific configuration files are provided as attachments to this document, as reported in Table 21. The test material is organized in two categories:

* Class CG: computer-generated content, containing CG1 and CG2 sub-categories,
* Class NC: natural content with estimated depth, containing NC1, NC2 and NC3 sub-categories.

The sequences have a common format as defined in the *Call for MPEG-I Visual Test Materials on 6DoF* [N17462] determining texture and depth representations, filenames and metadata. The views are numbered according to the ordering of the metadata files, counting from zero.

Note that the view numbering exists sometimes in a matrix version for the rig description and an ordinal version for the JSON file. Annex 2 “Source View label conversion” gives the correspondence between the two.

The test material is provided as a set of raw sequences, one per view and component (texture or depth). Texture and depth maps sequences characteristics are reported in the following sub-sections. The CG1 and NC1 sequences are named as follows:

v0\_texture\_4096x2048\_yuv420p10le.yuv

v0\_depth\_4096x2048\_yuv420p16le.yuv

using view 0 of ClassroomVideo as an example. The general format is:

**v**ViewNumber**\_**Component**\_**Width**x**Height**\_**VideoFormat**.yuv**

The attachment [A2] includes the json camera parameters to be used for all sequences. The attachment [A4] contains md5sums of the source material.

Table 1 provides a list of mandatory and optional sequences. Optional sequences are challenging content, deliberately difficult to handle. They are not meant for evaluation or promotion of the TMIV.

*Table 1: Mandatory and optional sequences*

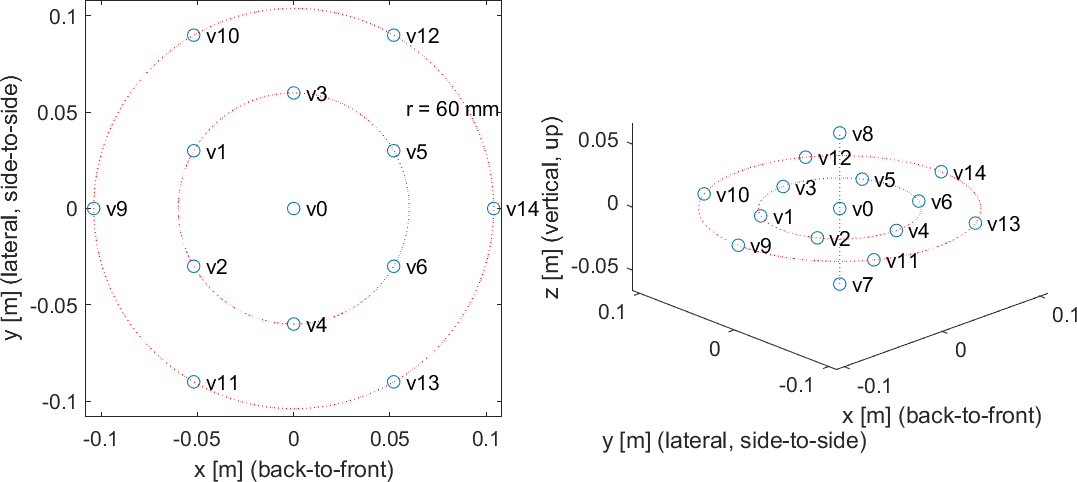
|  |  |  |
| --- | --- | --- |
| Mandatory sequences | CG1 – A | ClassroomVideo |
| CG1 – B | TechnicolorMuseum |
| CG1 – C | InterdigitalHijack |
| CG2 – J | OrangeKitchen |
| NC1 – D | TechnicolorPainter |
| NC1 – E | IntelFrog |
| NC2 – L | PoznanFencing |
| Optional sequences | CG1 – N | NokiaChess |
| NC1-P | PoznanCarpark |
| NC1-U | PoznanStreet |
| NC1-T | PoznanHall |

* 1. ***Computer-generated content***
     1. **ClassroomVideo**

The general characteristics of the ClassroomVideo sequence are summarized in Table 2. Source view positions are according to a hexagonally-packed circular disc with an additional top and bottom view, as shown in Figure 1.

*Table 2: Summary of the ClassroomVideo sequence*

|  |  |
| --- | --- |
| Category – Name | CG1 - A |
| Input contributions | m42415, m42756 and m42944 |
| Length & frame rate | 120 frames (30 fps) |
| Number of source views | 15 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits, normalized disparity in [0.8m, ) range |
| Source view resolution | 4096 × 2048 |
| View FoV & mapping | 360° × 180° ERP |
| Global FoV | 360° × 180° |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent /MPEG-I/Philips/ClassroomVideo/CE/  Data: v\*.zip |



*Figure 1: Visualization of the viewpoints of the ClassroomVideo sequence*

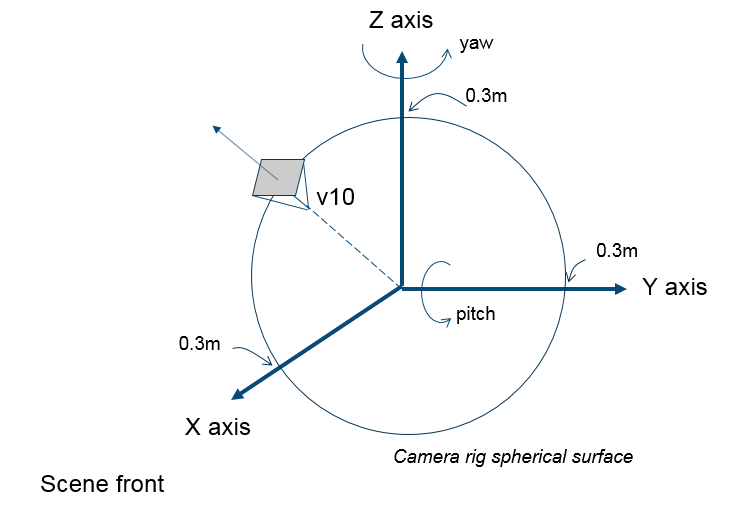
The viewing space volume is a spheroid centered at source view v0 eg (0, 0, 0) meter position, with equatorial radius 104 mm and polar distance 60 mm:

* + 1. **TechnicolorMuseum**

The general characteristics of the TechnicolorMuseum sequence are summarized in Table 3. The cameras are disposed on a spherical surface of 30 cm radius, and divergent in the direction of the sphere radius. Figure 2 provides the (X, Y, Z) coordinates and the spherical dimension, with an example using the 11th view. The metadata file comprising source and intermediate view positions is attachment A12 to this output document.

*Table 3: Summary of the TechnicolorMuseum sequence*

|  |  |
| --- | --- |
| Category - Name | CG1 - B |
| Input contribution | m42349 |
| Length & frame rate | 300 frames (30 fps) |
| Number of source views | 24 |
| Source view resolution | 2048 × 2048 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits, normalized disparity in [0.5m, 25m] range |
| View FoV & mapping | 180° × 180° ERP |
| Global FoV | 360° × 180° |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/ MPEG-I/Technicolor/TechnicolorMuseum/CE/  Data: TechnicolorMuseumV\*.zip |



*Figure 2: Coordinate system as used by 3D Audio and OMAF, with view 10 of the TechnicolorMuseum sequence superimposed*

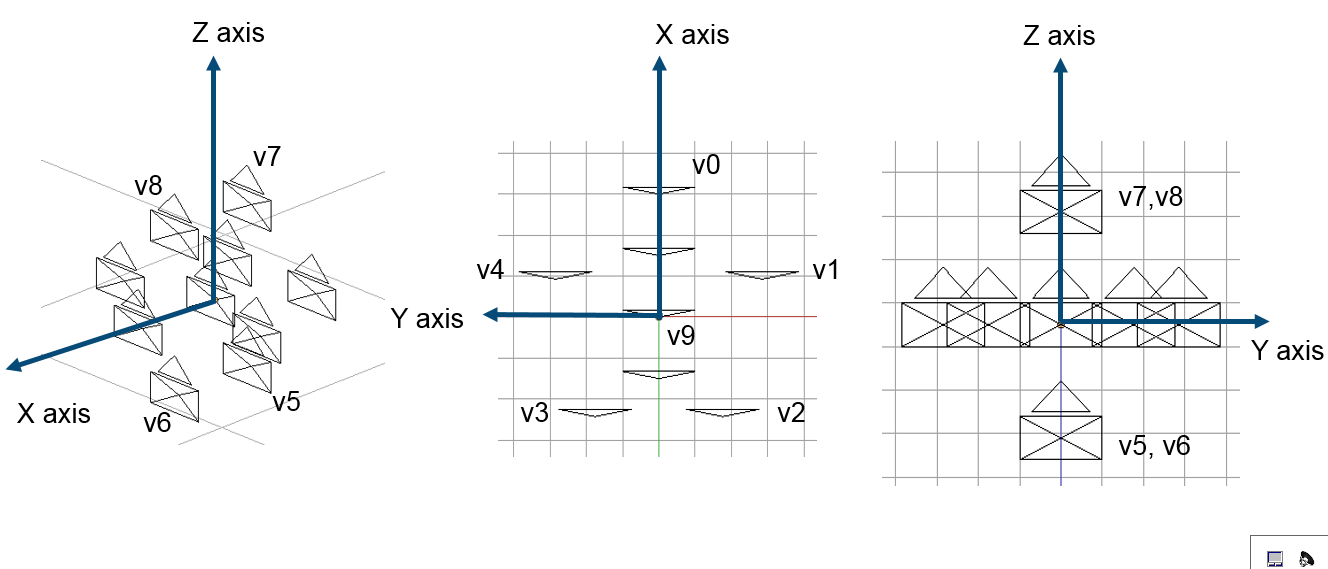
The viewing space volume is asphere centered at position [0, 0, 1.65] meter with a 300 mm radius:

* + 1. **InterdigitalHijack**

The general characteristics of the InterdigitalHijack sequence are summarized in Table 4. Figure 3 provides a visualization of the virtual camera rig in bias, top and front view respectively. The metadata file comprising source and intermediate view positions is in attachment [A2] of this output document.

*Table 4: Summary of the InterdigitalHijack sequence*

|  |  |
| --- | --- |
| Category - Name | CG1 - C |
| Input contribution | m42349 |
| Length & frame rate | 300 frames (30 fps) |
| Number of source views | 10 |
| Source view resolution | 4096 × 2048 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits, normalized disparity in [0.5m, 25m] range |
| View FoV & mapping | 180° × 90° ERP |
| Global FoV | 180° × 90° |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent /MPEG-I/Interdigital/InterdigitalHijack/  Data: vAll\_depth\_4096x2048\_yuv420p16le.zip  vAll\_texture\_4096x2048\_yuv420p10le.zip |



*Figure 3: Visualization of the view positions of the InterdigitalHijack sequence*

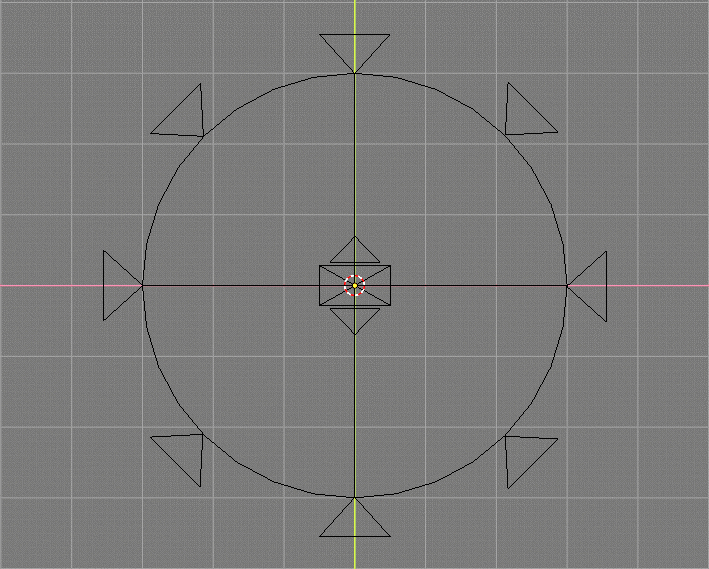
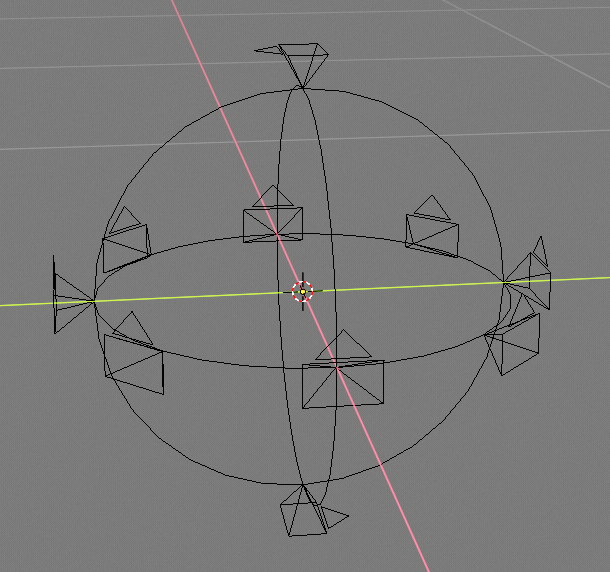
The viewing space volume is asphere centered at position [0, 0, 1.65] meter with a 300 mm radius:

* + 1. **NokiaChess**

The general characteristics of the NokiaChess sequence are summarized in *Table 5*. In total there are ten source cameras, laid out in a spherelike arrangement as illustrated in *Figure 4*. One camera in the constellation captures the top of the scene and another the bottom. The remaining eight cameras are pointing outwards to capture the rest of the scene. The radius of the spherical camera constellation is 30 cm. This sequence also comes with a ground truth pose-trace.

*Table 5: Characteristics of the NokiaChess sequence*

|  |  |
| --- | --- |
| Category - Name | CG1 - N |
| Input contributions | m50787 |
| Length & frame rate | 300 frames (30 fps) |
| Number of source views | 10 |
| Texture format | YUV 4:2:0 10-bits |
| Depth format | YUV 4:2:0 16-bits, normalized disparity in (0.1m,m) range |
| Source view resolution | 2048 × 2048 |
| View FoV & mapping | 180° × 180° ERP |
| Global FoV | 360° × 180° |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Nokia/MIV/NokiaChess  Data: v\*.tgz |



*Figure 4: visualization of the camera constellation for NokiaChess*

The viewing space volume is a sphere centered at position [-0.5, -0.5, 1.0] meter with a 300 mm radius:

* + 1. **OrangeKitchen**

The general characteristics of the OrangeKitchen sequence are summarized in *Table 8* and source view positions in Table 23. The captured views form a 5×5 planar array and are numbered v0-0 to v4-4 following left to right and top to bottom scan order.

*Table 8: Characteristics of the OrangeKitchen sequence*

|  |  |
| --- | --- |
| Category - Name | CG1 - J |
| Input contribution | m43318 |
| Length & frame rate | 97 frames (30 fps) |
| Number of source views | 25 (5x5) |
| Source view resolution | 1920x1080 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 10 bits |
| View FoV & mapping | 53.1° × 31.4° Rectilinear |
| Lens | 32 mm |
| Camera spacing | 20cm x 20cm |
| zNear | 2.2 |
| zFar | 7.2 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Orange/OrangeKitchen/CE  Data: v\*.zip |

The viewing space volume is a spheroid centered at position [0, -0.4, 0.4] meter, covering a vertical square of side equal to 0.8m and developed in the forward axis by 0.35m max.

* 1. ***Natural content with estimated depth*** 
     1. **TechnicolorPainter**

The general characteristics of the TechnicolorPainter sequence are summarized in Table 9 and source view naming in Table 22 form a 4x4 planar array and are numbered v0-0 to v3-3 following left to right and top to bottom scan order, as shown in Table 10. The refined depths proposed in [m47445] are used.

*Table 9: Summary of the TechnicolorPainter sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 - D |
| Input contributions | m40010, m40011, m43366 and m47445. |
| Length & frame rate | 300 frames (30 fps) |
| Number of source views | 16 (4x4) |
| Source view resolution | 2048 × 1088 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Technicolor/TechnicolorPainter/CE/  Data: TechnicolorPainterV\*.zip |

*Table 10: View numbering of the TechnicolorPainter camera array*

|  |  |  |  |
| --- | --- | --- | --- |
| v0-0 | v1-0 | v2-0 | v3-0 |
| v0-1 | v1-1 | v2-1 | v3-1 |
| v0-2 | v1-2 | v2-2 | v3-2 |
| v0-3 | v1-3 | v2-3 | v3-3 |

The viewing space volume is a spheroid centered at position [0, -0.35, -0.35] meter, covering a vertical square of side equal to 20cm and developed in the forward axis by 25cm max.

* + 1. **IntelFrog**

The general characteristics of the IntelFrog sequence are summarized in Table 11 and source view positions in Table 24. The captured views form a 15x1 line and are numbered v0-0 to v14-0 following left to right scan order. The refined depths proposed in [m47445] are used; these depths do not exist for extreme view positions v0 and v14 and therefore only the views from v1 to v13 are used.

*Table 11: Characteristics of the IntelFrog sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 - E |
| Input contribution | m43748, m44914 and m47445 |
| Length & frame rate | 300 frames (30fps) |
| Number of source views | 13 (13x1) |
| Source view resolution | 1920x1080 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| View FoV & mapping | 63.65° × 38.47° Rectilinear |
| Lens | 2.16 mm |
| Camera spacing | 3.675 cm |
| zNear | 0.3 |
| zFar | 1.62 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Intel/Frog/CE  Data: IntelFrog\_\*.zip |

The viewing space volume is a rectangle centered at position [0, 0, 0] meter with a 15cm width, 44.1cm length, and no z component.

* + 1. **PoznanFencing**

The general characteristics of the PoznanFencing sequence are summarized in *Table 12* and source view positions in Table 25. The captured views form a 10x1 linear arc and are numbered v0-0 to v9-0 following left to right scan order.

*Table 12: Characteristics of the PoznanFencing sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 - L |
| Input contribution | m38247 |
| Length & frame rate | 250 frames (25 fps) |
| Number of source views | 10 |
| Source view resolution | 1920x1080 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| View FoV & mapping | 63° × 48° |
| Lens | 4.5 mm |
| Camera spacing | 5 stereopairs (baseline: 22 cm) placed on arc (radius: 4 m),  angle between neighboring stereopairs: 15 degrees,  total angle of the system: 60 degrees |
| zNear | 3.5 |
| zFar | 7.0 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Poznan/Poznan\_Fencing2/CE  Data: PoznanFencing\_\*.zip |

* + 1. **PoznanStreet**

The general characteristics of the PoznanStreet sequence are summarized in Table X1. The captured views form a 9x1 line and are numbered v0 to v8 following left to right scan order.

*Table X1: Characteristics of the PoznanStreet sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 – U |
| Input contribution | m51598 |
| Length & frame rate | 250 frames (25fps) |
| Number of source views | 9 (9x1) |
| Source view resolution | 1920x1088 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| View FoV & mapping | 63° × 48° |
| Lens | 4.5 mm |
| Camera spacing | 13.75 cm |
| zNear | 34.5064 |
| zFar | 2760.511 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Poznan/PoznanStreet  Data: PoznanStreet\_\*.zip |

* + 1. **PoznanCarpark**

The general characteristics of the PoznanCarpark sequence are summarized in Table X2. The captured views form a 9x1 line and are numbered v0 to v8 following left to right scan order.

*Table X2: Characteristics of the PoznanCarpark sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 – P |
| Input contribution | m51598 |
| Length & frame rate | 250 frames (25fps) |
| Number of source views | 9 (9x1) |
| Source view resolution | 1920x1088 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| View FoV & mapping | 63° × 48° |
| Lens | 4.5 mm |
| Camera spacing | 13.75 cm |
| zNear | 34.5064 |
| zFar | 2760.511 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Poznan/PoznanCarpark  Data: PoznanCarpark\_\*.zip |

* + 1. **PoznanHall**

The general characteristics of the PoznanHall sequence are summarized in Table X3. The captured views form a 9x1 line and are numbered v0 to v8 following left to right scan order. Camera rig in the PoznanHall sequence was moving along the scene, but camera parameters remained the same for all frames.

*Table X3: Characteristics of the PoznanHall sequence*

|  |  |
| --- | --- |
| Category - Name | NC1 – T |
| Input contribution | m51598 |
| Length & frame rate | 500 frames (25fps) |
| Number of source views | 9 (9x1) |
| Source view resolution | 1920x1088 |
| Texture format | YUV 4:2:0 10 bits |
| Depth format | YUV 4:2:0 16 bits |
| View FoV & mapping | 63° × 48° |
| Lens | 4.5 mm |
| Camera spacing | 13.75 cm |
| zNear | 18.5064 |
| zFar | 2760.511 |
| Download | http://mpegfs.int-evry.fr/mpegcontent/ws-mpegcontent/MPEG-I/Poznan/PoznanHall  Data: PoznanHall\_\*.zip |

The viewing space volume is an arc centered at the origin with a 2.34m width, 6.89m length, and no z component.

1. **Software tools**

The referenced tools are listed in *Table 13*, with source code location, documentation and version number.

*Table 13: List of used tools*

|  |  |  |  |
| --- | --- | --- | --- |
| Tool name |  | Location | Tag/branch |
| TMIV | [w18795] | <https://gitlab.com/mpeg-i-visual/tmiv> | v3.0 |
| WS-PSNR | [w18069] | <https://gitlab.com/mpeg-i-visual/wspsnr> | v2.0.1 |
| HM |  | <https://hevc.hhi.fraunhofer.de/svn/svn_HEVCSoftware/tags/HM-16.16> | 16.16 |
| VMAF | [VMAF] | <https://github.com/Netflix/vmaf> | v1.3.14 |
| IV-PSNR | [w18709] | <https://gitlab.com/mpeg-i-visual/ivpsnr> | v1.0 |

* 1. ***HM***

HM 16.16 is used for the MIV anchor. For perspective sequences, it is used directly, while for omnidirectional sequences, it is used with 360Lib.

* 1. ***WS-PSNR***

WS-PSNR is a tool in used for computing WS-PSNR or PSNR for objective metrics on images and is used to compare coding and synthesis results against uncompressed source views. For the omnidirectional ERP sequences, computation is done according to §4.2 of [w17197] and is applied to Y, U and V components, but only the Y component is used for evaluation.

The second version of WS-PSNR adds support for perspective images and configuration files using the regular PSNR method.

* 1. ***VMAF***

Video Multimethod Assessment Fusion (VMAF) is an objective full-reference video quality metric. The v0.6.1 4K model that is included with this version of VMAF shall be used.

* 1. ***IV-PSNR***

The PSNR for Immersive Video (IV-PSNR) metric is a full-reference metric based on the PSNR. It includes two major changes: the pixel shift, that considers that edges of the objects in the synthesized view may be shifted due to rounding errors, and the global color shift, that considers that different input views may have various color characteristics.

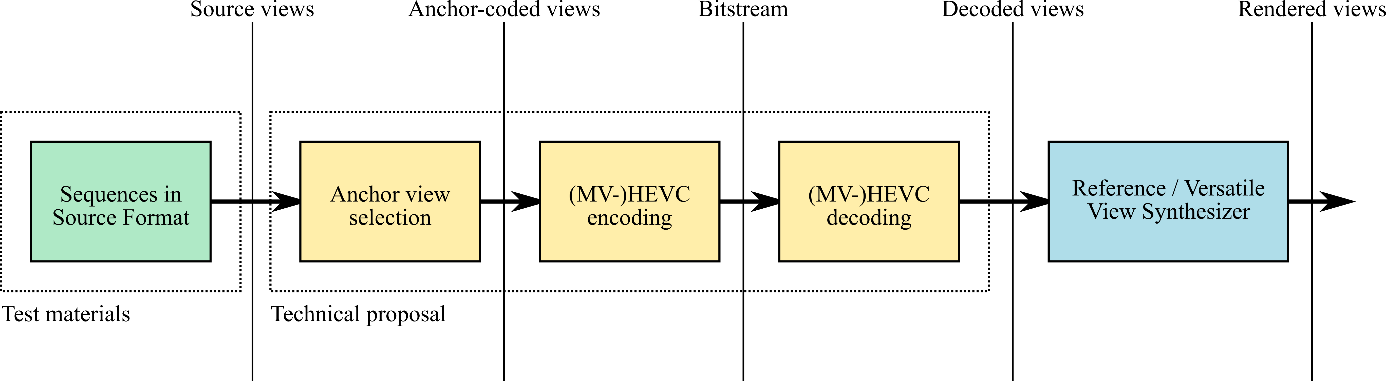
1. **Anchor definition**

Two anchors are considered to encode the multi-view sequences:

* **MIV anchor**: encoding of patch atlases with TMIV + HEVC,
* **MIV view anchor**: encoding of subset of source views with each full coded view represented in a separate atlas using a single patch, with TMIV + HEVC,

The description of the MIV anchor is provided in [w18470], and coding and synthesis specific details are provided in this section. The MIV view anchor uses a configuration that bypasses most of the MIV encoder.

The general structure of the MIV anchor is given in provided in [w18470].



*Figure 5: Definition of the anchor*

* 1. ***Coding of the anchor views***

To reduce the burden of anchor generation, without dropping any anchor, it has been decided at MPEG#128 meeting to create a configuration “17fr” with 17 frames only, to be used for MIV view, and MIV anchors. This configuration is used to compare the anchors against each other. The configuration “97fr”, with 97 frames is mandatory when proposing an improvement of the MIV anchor and is used (optionally) when proposing an improvement of the MIV View anchor. The frames to encode for each sequence are reflected in Table 14, for both “17fr” and “97fr” configurations. Specific details for each anchor are given in the following sub-sections. The attached configuration files [A5], as listed in annex 1, can be used as templates. The parameters that are changing from one sequence to another are listed in Table 15, for both MIV and MIV view anchors.

*Table 14:* *Start frames for each configuration.*

|  |  |  |  |
| --- | --- | --- | --- |
| Id | Sequence | “17fr” config. | “97fr” config. |
| CG1 – A | ClassroomVideo | 23 | 23 |
| CG1 – B | TechnicolorMuseum | 100 | 100 |
| CG1 – C | InterdigitalHijack | 0 | 0 |
| CG1 – N | NokiaChess | 60 | 60 |
| CG2 – J | OrangeKitchen | 0 | 0 |
| NC1 – D | TechnicolorPainter | 40 | 40 |
| NC1 – E | IntelFrog | 135 | 135 |
| NC2 – L | PoznanFencing | 30 | 30 |
| NC1-P | PoznanCarpark | 130 | 115 |
| NC1-U | PoznanStreet | 225 | 145 |
| NC1-T | PoznanHall | 80 | 0 |

*Table 15: Sequence dependent parameters.*

|  |  |  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| **Parameter** | **SA** | **SB** | **SC** | **SD** | **SE** | **SJ** | **SL** | **SN** | **SP** | **ST** | **SU** |
| numGroups | 1 | 1 | 1 | 2 | 2 | 2 | 2 | 1 | 2 | 2 | 2 |
| SourceGeometryBitDepth | 16 | 16 | 16 | 16 | 16 | 10 | 16 | 16 | 16 | 16 | 16 |

* + 1. **Coding for MIV anchor**

The coding of the MIV anchor is explained in [w18470]. For each video sequence, two sets of QP points are considered, medium and low, corresponding respectively to QP1, QP2, QP3, QP4, and QP2, QP3, QP4, QP5, as defined in Table 16.

*Table 16: QPs used for depth and texture*

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | QP1 | QP2 | QP3 | QP4 | QP5 |
| Texture | 22 | 27 | 32 | 37 | 42 |
| Depth | 4 | 7 | 11 | 15 | 20 |

The anchor encodes all source views with depths input resolution as reported in tables of section 2 (16 bits for all sequences except OrangeKitchen). The anchor bitstreams themselves include decoded picture hashes for automatic consistency checking.

* + 1. **Coding for MIV view anchor**

The same parameters are used as for the MIV anchor except for the following:

* ViewOptimizerMethod = NoViewOptimizer
* SourceCameraNames = Anchor-coded view as shown in Table 18
* Depth QPs as shown in Table 17.

The NoViewOptimizer component forwards all source views as “basic” and none as “additional” such that the atlas constructor creates trivial atlases: one per source view and one big patch for per atlas.

*Table 18: QPs used for depth and texture*

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | QP1 | QP2 | QP3 | QP4 | QP5 |
| Texture | 22 | 27 | 32 | 37 | 42 |
| Depth | 9 | 9 | 14 | 17 | 21 |

*Table 19: Anchor-coded views per class*

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| Sequence Name | Format | # of source views | # of anchor-coded views | Anchor-coded views |
| ClassroomVideo | ERP | 15 | 9 | v0, v7…v14 |
| TechnicolorMuseum | ERP | 24 | 8 | v0, v1, v4, v8, v11, v12, v13, v17 |
| InterdigitalHijack | frac-ERP | 10 | 5 | v1, v4, v5, v8, v9 |
| TechnicolorPainter | perspective | 16 | 8 | v0, v3, v5, v6, v9, v10, v12, v15 |
| IntelFrog | perspective | 13 | 7 | v1, v3, v5, v7, v9, v11, v13 |
| OrangeKitchen | perspective | 25 | 9 | v00, v02, v04, v10, v12, v14, v20, v22, v24 |
| PoznanFencing | perspective | 10 | 5 | v00, v02, v04, v06, v08 |
| NokiaChess | semi-ERP | 10 | 6 | v0, v1, v3, v5, v7, v9 |
| PoznanStreet | perspective | 9 | 5 | v0, v2, v4, v6, v8 |
| PoznanCarpark | perspective | 9 | 5 | v0, v2, v4, v6, v8 |
| PoznanHall | perspective | 9 | 5 | v0, v2, v4, v6, v8 |

* 1. ***Synthesis of the intermediate views***

Both for objective and subjective testing, a range of frames of each sequence are synthesized at source positions. For the synthesis, all decoded atlases are used as input of the view synthesis algorithm. For the objective evaluation, the frames as reported in Table 14 are used for view synthesis.

Proposals are not required to code views corresponding to all anchor-coded views but are required to be able to generate viewport and omnidirectional or perspective video sequences for any intermediate view position in the designated range for each test sequence. The field of view for ERP (e.g. 180° or 360° degrees) will be the same as the source content.

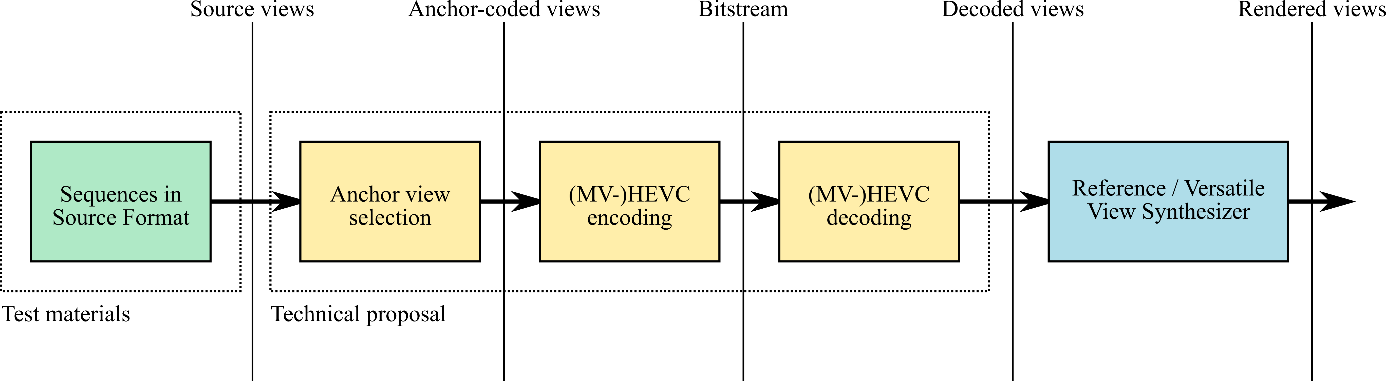
Specific details for each anchor are given in the following sub-sections.

The synthesis of the MIV anchor is explained in [w18795]. The format of each synthesized view is an omnidirectional image with equirectangular projection with the same angular resolution (pixels / degree) for ERP or semi-ERP test materials, and a linear perspective projection for linear perspective input content. The synthesis result is 10-bit YUV 4:2:0 format for subjective evaluation and 10-bit YUV 4:2:0 for objective evaluation.

Inpainting of invalid pixels is used for both subjective and objective testing.

1. **Evaluation of proposals**

The general structure of the anchor generation is represented in Figure 5. It consists of encoding multiple views, with the anchor coded views possibly being a subset of the available source views. The resulting bitstream is decoded and provides decoded views. From this set of decoded views, non-coded source views and intermediate views are synthesized. Only objective and subjective results on mandatory sequences are required for an adoption of a proposal. Additional results obtained on optional sequences can be provided as additional information.



*Figure 6: Definition of the anchor*

* 1. ***Subjective quality evaluation***

For subjective viewing, each sequence is also synthesized according to a set of pose traces. A pose trace specifies for each frame the position and orientation of the viewport to synthesize. Each pose trace is stored as a comma-separated table with position (X, Y, Z) and orientation (Yaw, Pitch, Roll) columns and exactly one row per frame of the sequence. The format of each synthesized view is an image with perspective projection with at most 2048 × 2048 pixels resolution, at most 90-degree field of view and 10-bit YUV 4:2:0 color format. The purpose is to mimic natural viewing on a head-mounted display (HMD) while using offline tools and a 2D monitor.

Because of the large difference in visual comfort between a viewer that voluntarily initiates head motion versus a viewer watching the same viewport on a 2D monitor, pose traces will have a small amount of motion. For each sequence there are three pose traces – named *X*p01, *X*p02 and *X*p03 – which are meant to represent a diversity of natural head movement compliant with the overall dimension of the capture rig, as indicated in Table 21. Attachment [A3] contains all pose traces. The TMIV decoder is configured to extend the video to 300 frames by mirroring the 97-frame sequences. ClassroomVideo pose traces have been replaced by pose traces that are 300 frames long. The other pose traces are the same as for the CfP [w18145].

It is meaningful to define the pose traces according to the conditions of capture, and typically to define the related path within the volume of the camera rig. It is convenient to formulate this range as a volume in 3D space, as described per sequence in Section 2.

For adoption of a proposed method, the proponent must:

* be able to show any pose trace of the proposed method, during a viewing session.
* be able to show, during the presentation of the contribution, any pose trace, in a side-by-side mp4 format including the anchor, and make it clear what the bitrate and pixel-rate differences with the anchor are.

The command line to be used to generate the side-by-side pose trace is the following:

*ffmpeg.exe -f rawvideo -pix\_fmt yuv420p10le -s:v {width}x{height} -r {fps} -I {anchor yuv} -f rawvideo -pix\_fmt yuv420p10le -s:v {width}x{height} -r {fps} -i {proposed yuv} -profile:v high -c:v libx264 -qp 10 -filter\_complex“"[0:v][1:v]hstack=inputs=”" {output mp4}*

* 1. ***Objective evaluation***

The following definitions apply:

* “**Coded source view**” corresponds to a source view that is coded by the anchor,
* “**Synthesized view**” corresponds to a source view that is synthesized (interpolated) by the anchor using multiple decoded source views, always excluding the target view.

Coded views (texture or depth) are evaluated on the frames of each of the sequences as reported in Table 14. The original view is the uncompressed source view. Synthesized views are evaluated on the same frames.

The new methods should be compared with the anchor coding results, by reporting the metrics as in Table 20. The columns PSNR diff., VMAF diff., and IV-PSNR diff. respectively represent the differences for the corresponding objective metrics, between the original source view and the synthesized view, averaged among the 5 QPs. All metrics are mandatory.

*Table 20: Presentation of the results.*

|  |  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Configuration | Sequence | Coded source view BD rate | Synthesized view BD rate | Encoding time | Decoding time |  | Synthesis time | PSNR diff. | VMAF diff. | IV-PSNR diff. |
| Random Access | Sequence 1 | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |
| Low bitrate | Sequence 2 | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |
| **Average** | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |
| Random Access | Sequence 1 | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |
| High bitrate | Sequence 2 | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |
|  | **Average** | x% | x% | x% | x% |  | x% | xdB | xdB | xdB |

For all test classes, WS-PSNR based BD-rate values will be provided for synthesized source views. For perspective views WS-PSNR reduces to regular PSNR. BD-rate values for coded source views will only be provided for the subset of views coded both by the anchor and proposal.

The comparison of proponents with the anchors will be expressed in terms of BD rate computed on low- and medium bitrate rate-distortion RD curves.

* **Coded source view BD rate**, only when anchor and proposal code the same set of views, obtained from:
  + For the anchor RD curve:
    - The average over each view and frames (Table 14) of the WS-PSNR (for ERP and semi-ERP content) or PSNR (for perspective content) between the coded view (coded texture) and the corresponding source view,
    - The total bitrate required to encode the views including texture and depths for all frames.
  + For the proponent’s RD curve:
    - The average over each view and all frames (Table 14) of the WS-PSNR (for ERP and semi-ERP content) or PSNR (for perspective content) between the proponent’s view (coded texture) corresponding to anchor coded view positions, and the source view,
    - The total bitrate of the proponent’s bitstream for all frames including texture, depth and metadata.
* **Synthesized view BD rate,** obtained from:
  + For the anchor RD curve:
    - The average over each source view and specified frames (Table 14) of the WS-PSNR (for ERP and semi-ERP content) or PSNR (for perspective content) between the intermediate view synthesized from decoded views and the original/non-compressed source views,
    - The total bitrate required to encode the views (including depths) for all frames.
  + For the proponent’s RD curve:
    - The average over each source view and specified frames (Table 14) of the WS-PSNR (for ERP and semi-ERP content) or PSNR (for perspective content) between the proponent’s synthesized intermediate view and the original/non-compressed source view,
    - The total bitrate of the proponent’s bitstream for all frames.

The reporting template, provided as attachment, should be used for all contributions. This template will compare a proposal with all anchors. Because TMIV makes use of floating-point operations, it is important to report the compiler and operating system that are used for evaluation. Preferred compilers are GCC 7 or newer and VC15. The TMIV software should be built in Release mode and the cMake project should be generated using one of the included build scripts.

* 1. ***Pixel rate evaluation***

Objective evaluation criteria include pixel rate, which is included in the reporting template. Contributions are required to provide pixel rate for each tested sequence. Proponents should report results which they believe are the most optimal compromise between pixel rate and quality. To provide a meaningful reference for pixel rate values, the following constraints are defined:

**Low pixel rate test condition constraints:**

* The combined maximum luma sample rate across all decoders is maximally 1,069,547,520 samples per second (e.g. 32 MP @ 30 fps, corresponding to HEVC Main 10 profile @ Level 5.2)
* Each decoder instantiation is constrained to a maximum luma picture size of 8,912,896 pixels (e.g. 4096 x 2048, corresponding to HEVC Main 10 profile @ Level 5.2).
* The maximum number of simultaneous decoder instantiations is four.

**High pixel rate test condition constraints:**

* The combined maximum luma sample rate across all decoders is maximally 4,278,190,080 samples per second (e.g. 128 MP @ 30 fps, corresponding to HEVC Main 10 profile @ Level 6.2)
* Each decoder instantiation is constrained to a maximum luma picture size of 35,651,584 pixels (e.g. 8192 x 4096, corresponding to HEVC Main 10 profile @ Level 6.2).
* The maximum number of simultaneous decoder instantiations is four.

These conditions are orthogonal to low/high bitrate conditions and apply in principle to the MIV anchor and the MIV view anchor.

* 1. ***Runtimes evaluation***

Runtimes should be reported for anchors and proposals (corresponding cells in the xls template are mentioned):

* Atlas generation (incl. all preprocessing), cells M267 to M271 and AA267 to AA271.
* HM encoding of texture and depth atlases, cells M4 to M128 and AA4 to AA128, M140 to M264 and AA140 to AA264.
* HM decoding of texture and depth atlases, cells N4 to N128 and AB4 to AB128, N140 to N264 and AB140 to AB264.
* Rendering (incl. all postprocessing), cells N285 to N409 and AB285 to AB409.

The reference software includes measurement of CPU runtime, excluding loading from disk and writing to disk. Proposals should include a similar runtime measurement.

It is reminded that the proponent has to fill the runtimes for both anchor and proposed method, so that the delta between anchor and proposal runtimes has a meaning.

1. **References**

[VMAF] [vmaf: Perceptual video quality assessment based on multi-method fusion](https://github.com/Netflix/vmaf), Netflix, Inc., 2017-07-14.

[w18068] Reference View Synthesizer (RVS) manual, ISO/IEC JTC1/SC29/WG11 MPEG/N18068, October 2018, Macau SAR, China.

[w18069] ERP WS-PSNR manual, ISO/IEC JTC1/SC29/WG11 MPEG/N18069, October 2018, Macau SAR, China.

[w17197] Algorithm descriptions of projection format conversion and video quality metrics in 360Lib Version 5, JVET-H1004, ISO/IEC JTC1/SC29/WG11 MPEG/N17197, October 2017, Macau SAR, China.

[w18145] Call for Proposals on 3DoF+ Visual, ISO/IEC JTC1/SC29/WG11 MPEG/N18145, January 2019, Marrakesh, Morocco.

[w18795] Test Model 3 for Immersive Video, ISO/IEC JTC1/SC29/WG11 MPEG/N18795, October 2019, Geneva, Switzerland.

[w18709] Software manual of IV-PSNR for Immersive Video, ISO/IEC JTC1/SC29/WG11 MPEG/N18709, July 2019, Gothenburg, Sweden.

**Annex 1: List of attachments**

Table 21 provides an overview of files that are provided together with this document. Attachments [A1], [A2], [A3] and [A4] are also included as part of the TMIV reference software.

*Table 21: List of attachments to this document*

|  |  |  |
| --- | --- | --- |
| ID | Filename | Short description |
| [A1] | template.zip | Reporting xls template |
| [A2] | tmiv\_camparam.zip | Metadata files according to the updated format [w18068] with source and intermediate view positions for all sequences (omnidirectional and perspective) |
| [A3] | tmiv\_posetraces.zip | Three pose traces per sequence |
| [A4] | source\_md5.zip | MD5 sums for all source data |
| [A5] | tmiv\_configs.zip | Template configuration files for SA |

**Annex 2: Source view label conversion**

*Table 22: View naming of the TechnicolorPainter sequence*

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| Original view name | Json view name | Original view name | Json view name | Original view name | Json view name | Original view name | Json view name |
| v0-0 | v0 | v1-0 | v1 | v2-0 | v2 | v3-0 | v3 |
| v0-1 | v4 | v1-1 | v5 | v2-1 | v6 | v3-1 | v7 |
| v0-2 | v8 | v1-2 | v9 | v2-2 | v10 | v3-2 | v11 |
| v0-3 | v12 | v1-3 | v13 | v2-3 | v14 | v3-3 | v15 |

*Table 23: View naming of the OrangeKitchen sequence*

|  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Original view name | Json view name | Original view name | Json view name | Original view name | Json view name | Original view name | Json view name | Original view name | Json view name |
| v0-0 | v00 | v0-1 | v05 | v0-2 | v10 | v0-3 | v15 | v0-4 | v20 |
| v1-0 | v01 | v1-1 | v06 | v1-2 | v11 | v1-3 | v16 | v1-4 | v21 |
| v2-0 | v02 | v2-1 | v07 | v2-2 | v12 | v2-3 | v17 | v2-4 | v22 |
| v3-0 | v03 | v3-1 | v08 | v3-2 | v13 | v3-3 | v18 | v3-4 | v23 |
| v4-0 | v04 | v4-1 | v09 | v4-2 | v14 | v4-3 | v19 | v4-4 | v24 |

*Table 24: View naming of the IntelFrog sequence*

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| Original view name | Json view name | Original view name | Json view name | Original view name | Json view name | Original view name | Json view name |
| cam00 | v14 | cam04 | v10 | cam08 | v06 | cam12 | v02 |
| cam01 | v13 | cam05 | v09 | cam09 | v05 | cam13 | v01 |
| cam02 | v12 | cam06 | v08 | cam10 | v04 | cam14 | v00 |
| cam03 | v11 | cam07 | v07 | cam11 | v03 |  |  |

*Table 25: View naming of the PoznanFencing sequence*

|  |  |  |  |
| --- | --- | --- | --- |
| Original view name | Json view name | Original view name | Json view name |
| v0-0 | v00 | v5-0 | v05 |
| v1-0 | v01 | v6-0 | v06 |
| v2-0 | v02 | v7-0 | v07 |
| v3-0 | v03 | v8-0 | v08 |
| v4-0 | v04 | v9-0 | v09 |