

# 3D Visual Grounding with Transformers

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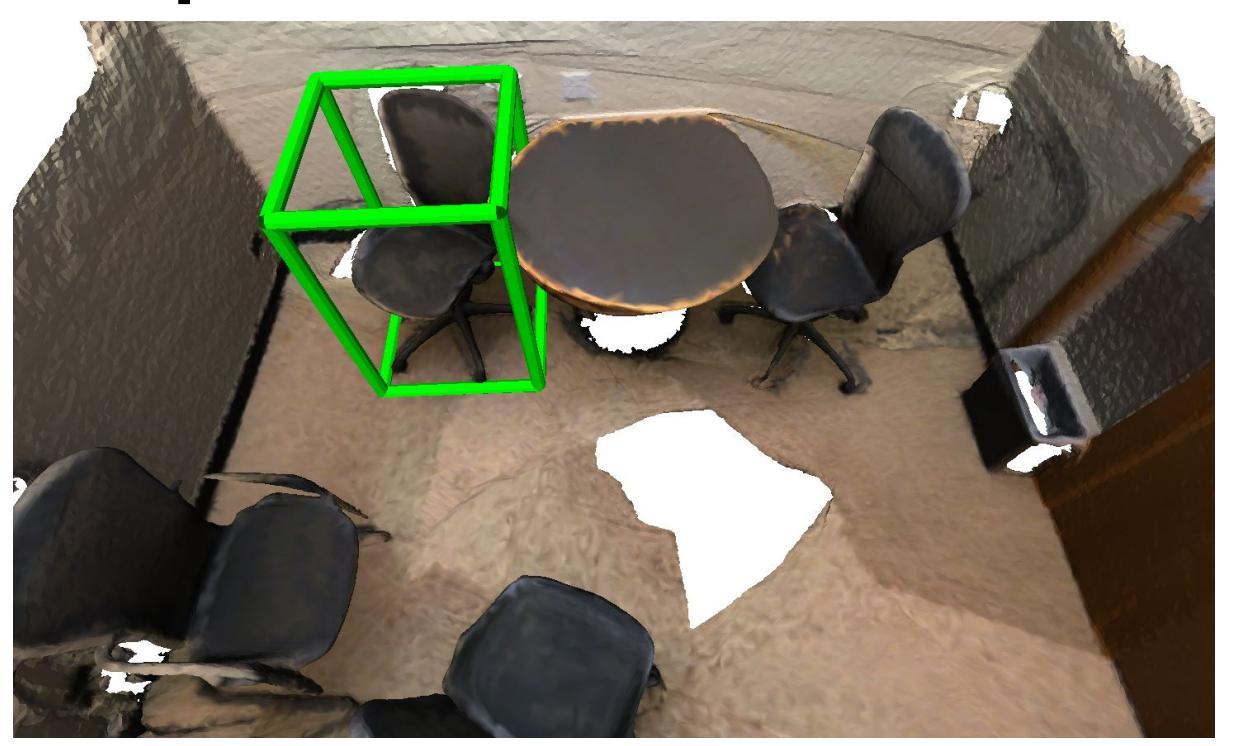
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## Introduction

### Inputs:



### Output:



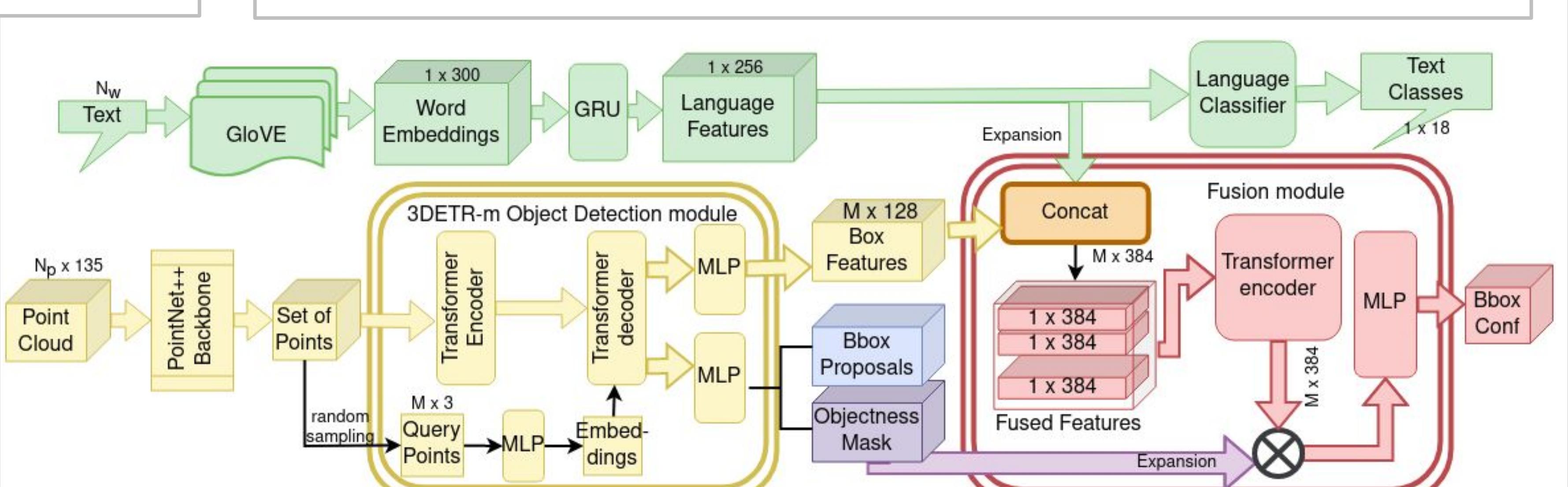
There is an outlet in the wall next to the black office chair. The office chair is next to a round table.

3D visual grounding is the task of localizing a target object in a 3D scene given a natural language description. The task involves 3D object detection, natural language encoding and the final fusion and localization of the target object.

## Idea

We use a transformers-based architecture to fully utilize the contextual clues. Since transformers can naturally operate on variable sized inputs such as point cloud and encode long-range contexts that enrich the visual grounding task.

For 3D object detection and feature generation the **3DETR-m** transformer introduced into the ScanRefer architecture. Additionally, we used a **vanilla transformer encoder** for the matching of the textual and visual features since it is uniquely suited to capture the relevant context. We also experimented with replacing the GRU model with a transformer language encoder **BERT**.



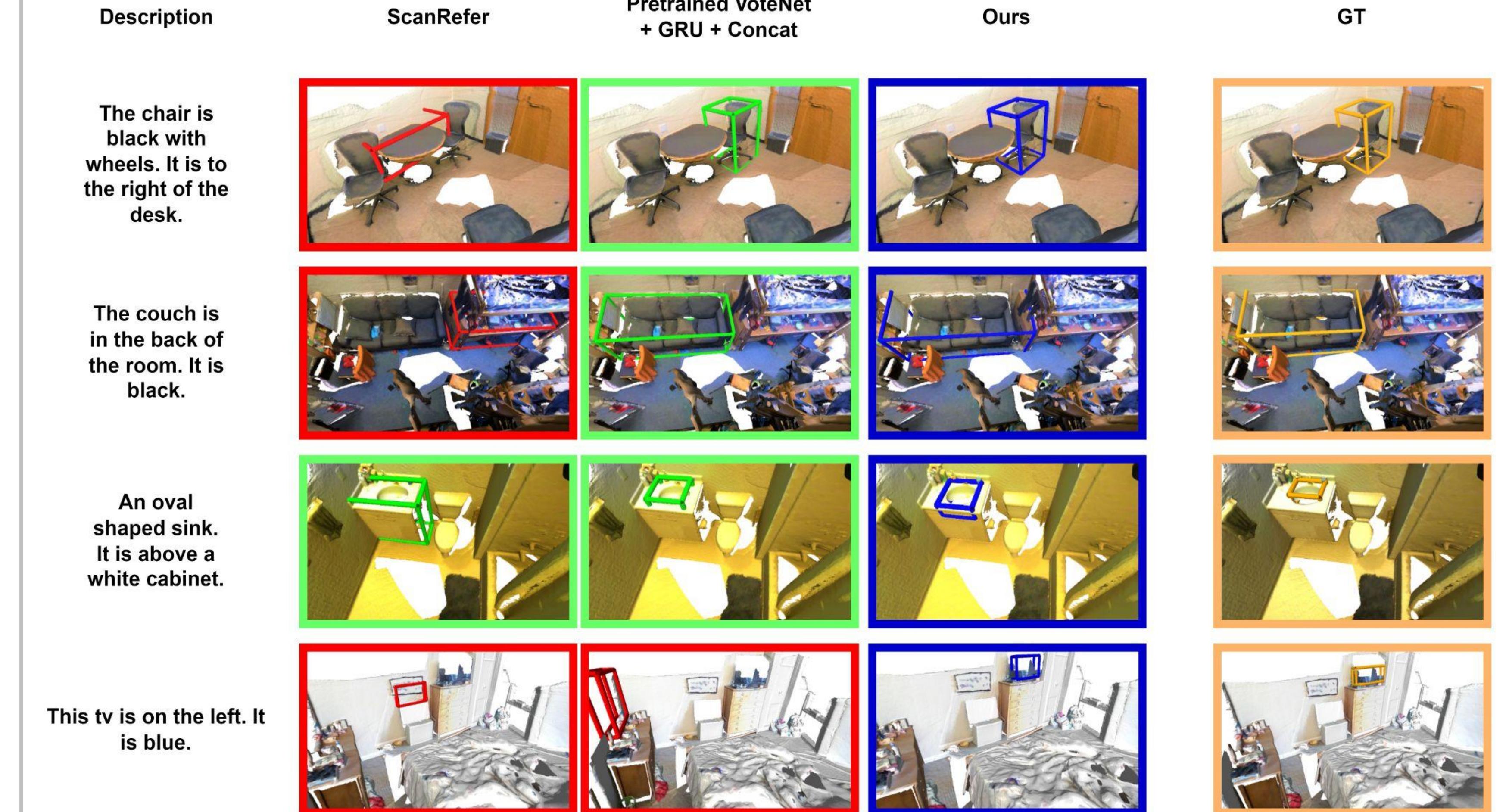
## Ablation Study

Model	Acc@0.25	Acc@0.5
pretrained VoteNet + GRU + Concat	37.11	25.21
pretrained 3DETR-m + GRU + Concat	35.00	25.50

Model	Acc@0.25	Acc@0.5
ScanRefer (VoteNet + GRU + Concat)	35.66	22.01
VoteNet + <b>BERT</b> Layer 12 + Concat	34.22	21.10

Model	Acc@0.25	Acc@0.5
pretrained 3DETR-m + GRU + <b>Concat</b>	35.00	25.50
pretrained 3DETR-m + GRU + <b>vTransformer Layer 5</b>	37.08	26.56

## Qualitative Results



Model	Acc@0.25	Acc@0.5	Duration
ScanRefer (VoteNet + GRU + Concat)	37.05	23.93	25h
Pretrained VoteNet + GRU + Concat	37.11	25.21	4h 17min
Ours (Pretrained 3DETR-m + GRU + vTransformer)	37.08	26.56	9h 20min

Check out our paper and project page for more results and comparisons!  
<https://github.com/flo-stilz/3D-Visual-Grounding-with-Transformers>