Path to Neural Networks II

Image courtesy Vogel et al. [2018], Gharbi et al. [2019]

Today's Menu

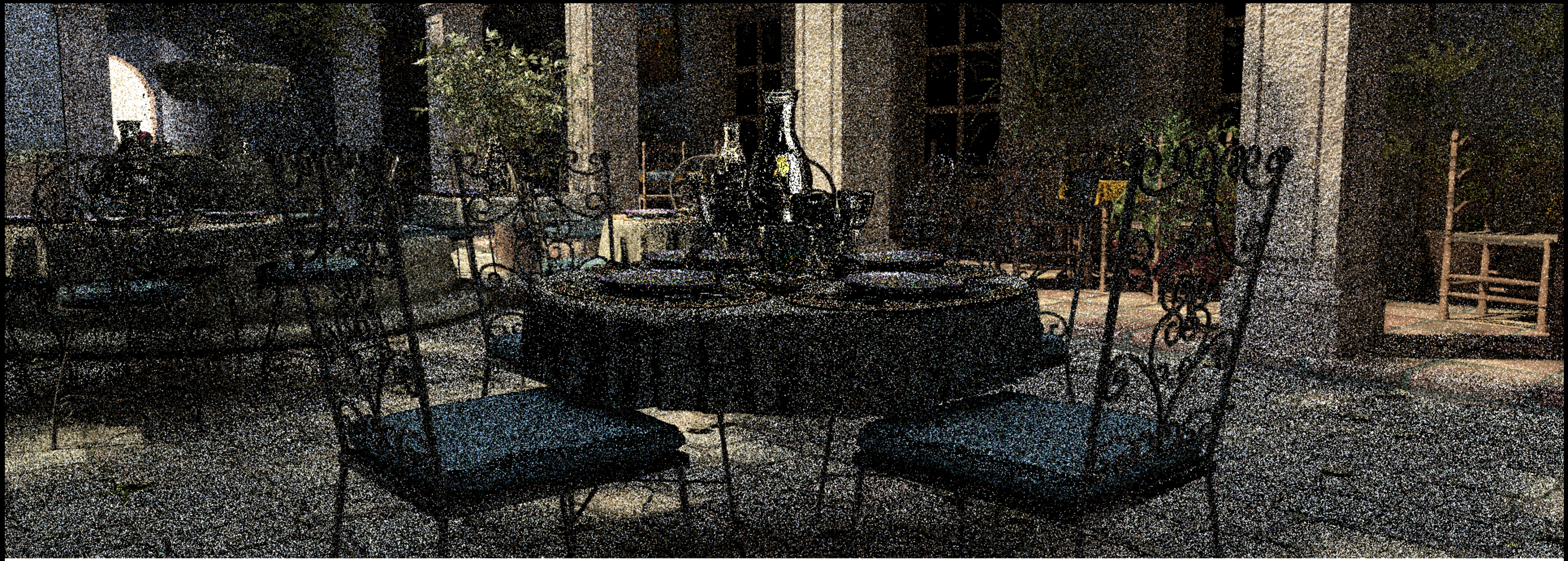
Sample-based denoising

CNN-based approach to generate blue-noise samples

Normalizing Flows

Path guiding using Normalizing Flows

Recap



input Monte Carlo (8 samples/pixel)

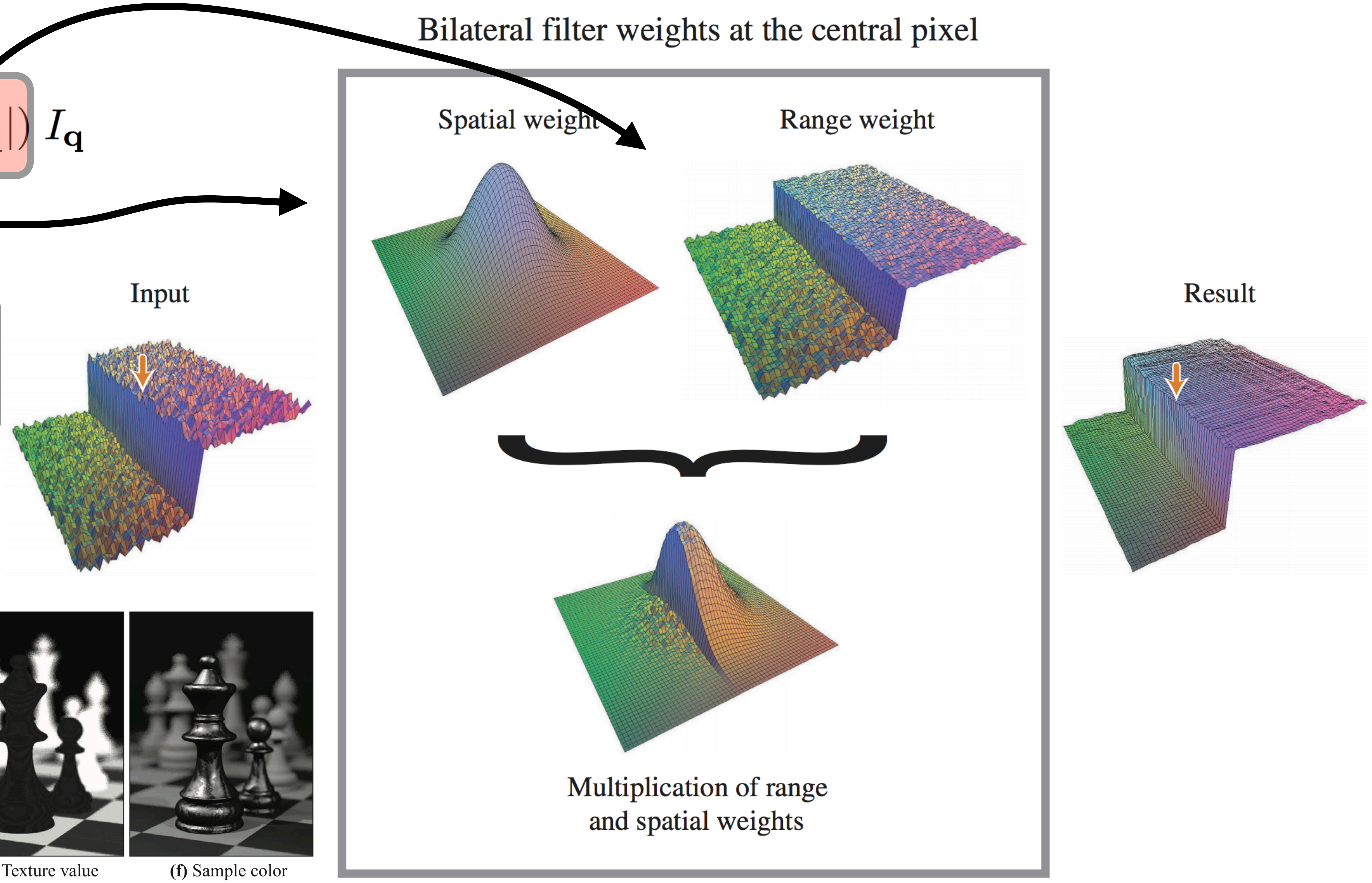
after RPF (8 samples/pixel)

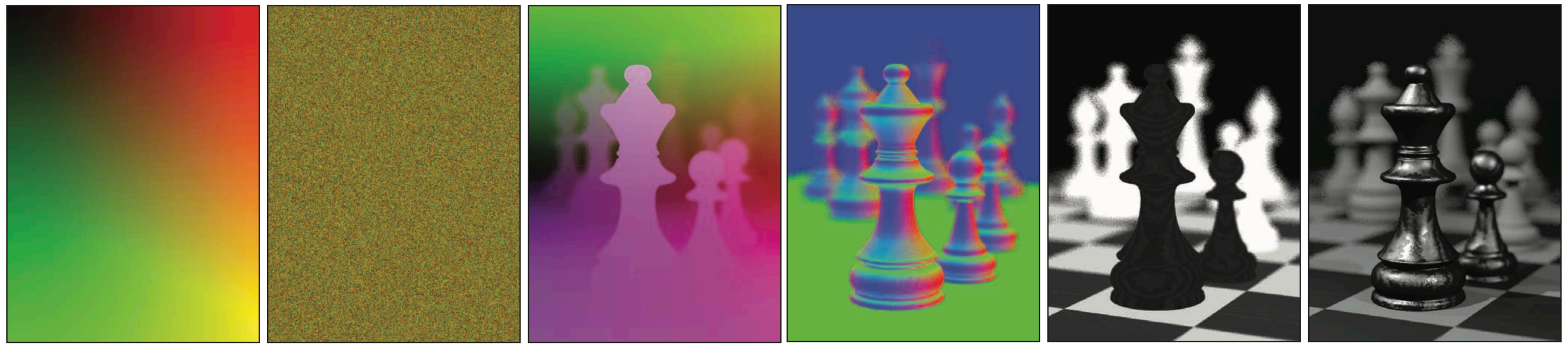
(a) Input MC (8 spp) **(b)** Dependency on (u, v) **(c)** Our approach (RPF)

Bilateral Filtering

$$BF[I]_{\mathbf{p}} = \frac{1}{W_{\mathbf{p}}} \sum_{\mathbf{q} \in \mathcal{S}} G_{\sigma_s}(\|\mathbf{p} - \mathbf{q}\|) \, G_{\sigma_r}(|I_{\mathbf{p}} - I_{\mathbf{q}}|) \, I_{\mathbf{q}}$$

$$W_{\mathbf{p}} = \sum_{\mathbf{q} \in \mathcal{S}} G_{\sigma_s}(\|\mathbf{p} - \mathbf{q}\|) \, G_{\sigma_r}(|I_{\mathbf{p}} - I_{\mathbf{q}}|)$$



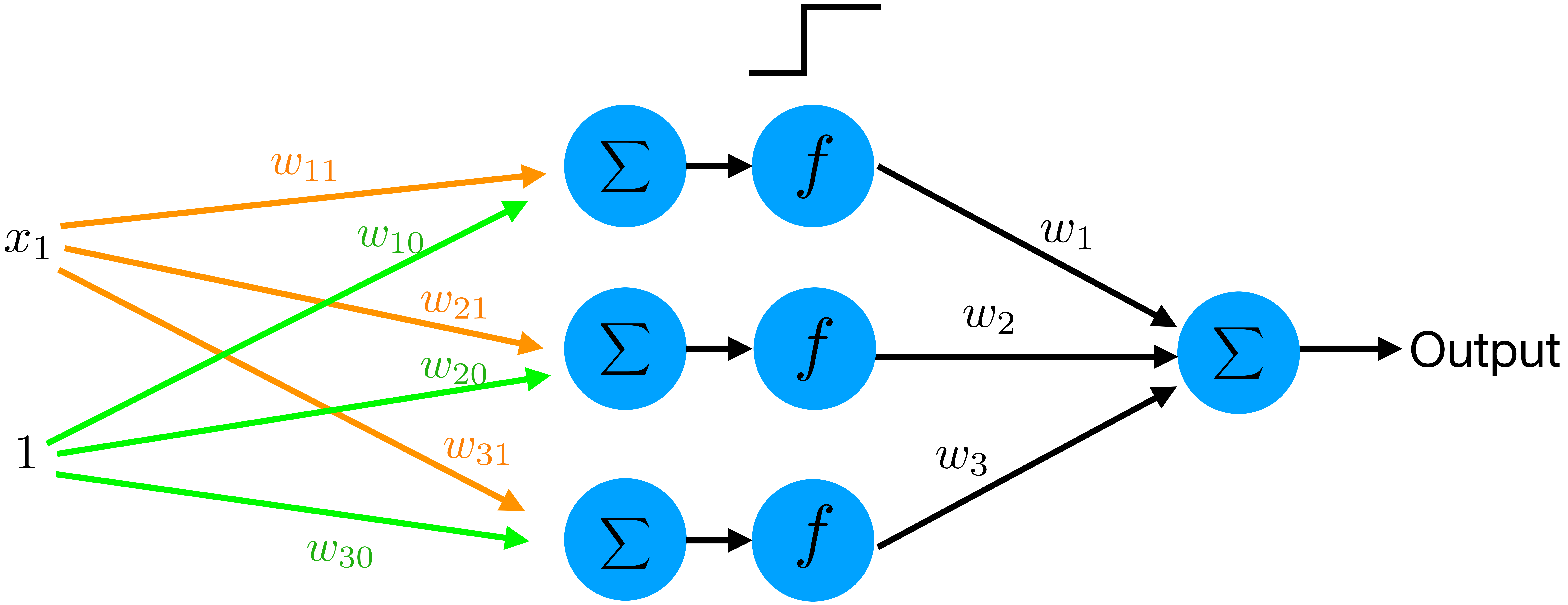


(a) Screen position (b) Random parameters (c) World space coords. (d) Surface normals (e) Texture value (f) Sample color

Bilateral Filtering of Features

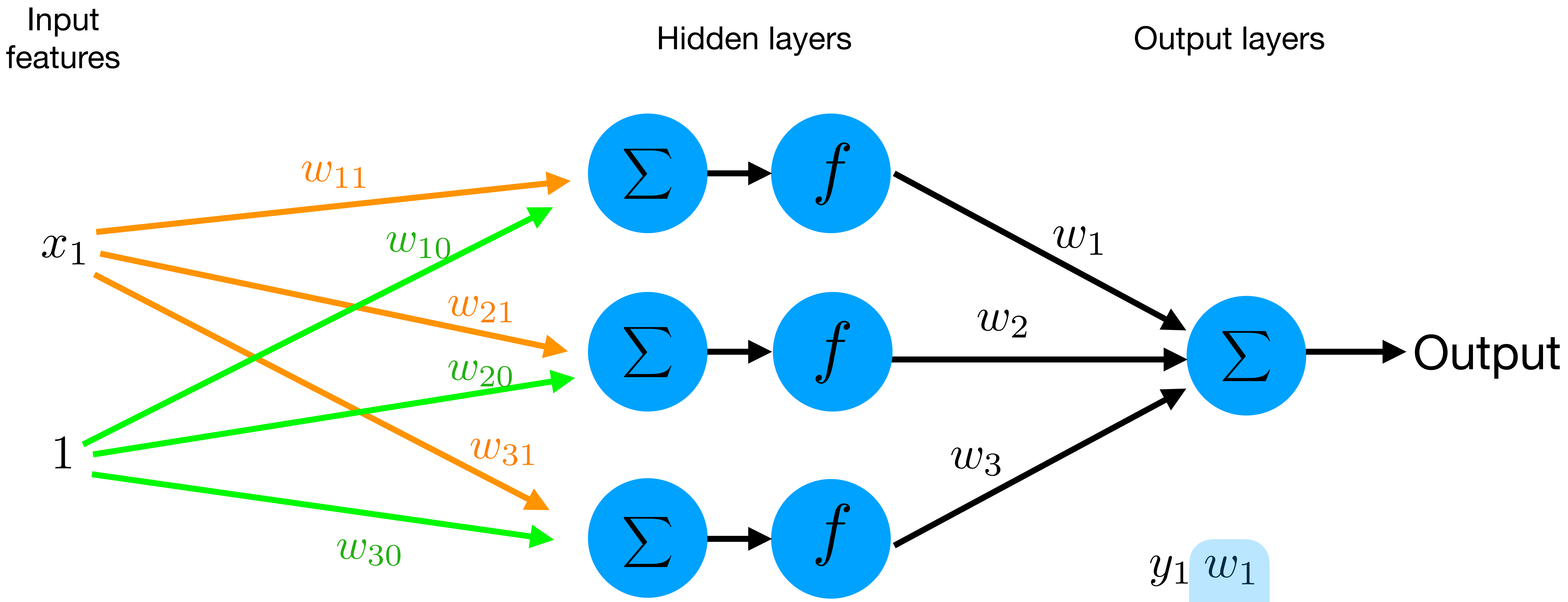
$$w_{ij} = \exp[-\frac{1}{2\sigma_{\mathbf{p}}^2} \sum_{1 \leq k \leq 2} (\bar{\mathbf{p}}_{i,k} - \bar{\mathbf{p}}_{j,k})^2] \times$$
$$\exp[-\frac{1}{2\sigma_{\mathbf{c}}^2} \sum_{1 \leq k \leq 3} \alpha_k (\bar{\mathbf{c}}_{i,k} - \bar{\mathbf{c}}_{j,k})^2] \times$$
$$\exp[-\frac{1}{2\sigma_{\mathbf{f}}^2} \sum_{1 \leq k \leq m} \beta_k (\bar{\mathbf{f}}_{i,k} - \bar{\mathbf{f}}_{j,k})^2],$$

Multi-layer Perceptron



$$y_1 = f(x_1 w_{11} + w_{10})$$
$$y_2 = f(x_1 w_{21} + w_{20})$$
$$y_3 = f(x_1 w_{31} + w_{30})$$

Multi-layer Perceptron



$y_1 = f(x_1 w_{11} + w_{10})$
$y_2 = f(x_1 w_{21} + w_{20})$
$y_3 = f(x_1 w_{31} + w_{30})$

$y_1 w_1$
$y_2 w_2$
$y_3 w_3$

Filter weights

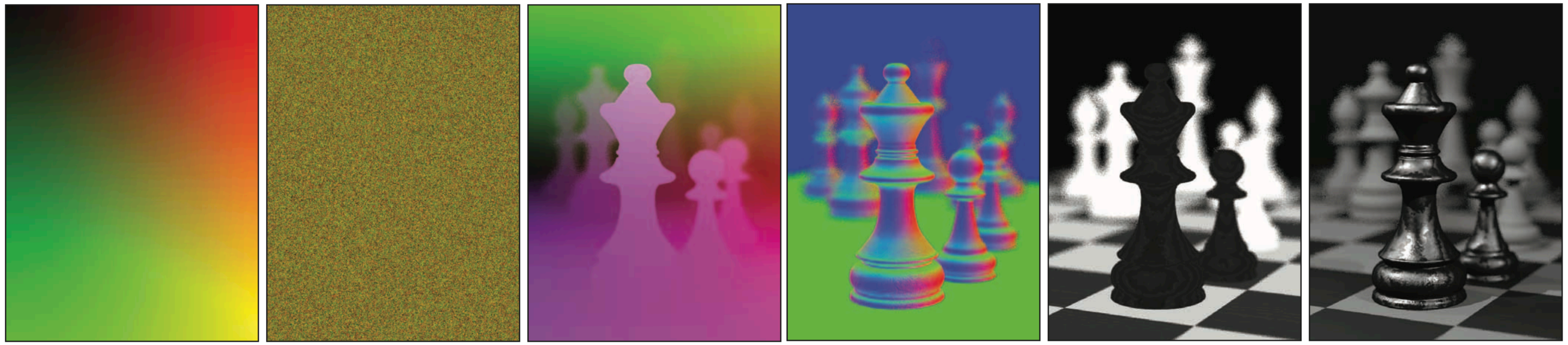
For cross Bilateral filters:

$$d_{i,j} = \exp\left[-\frac{\|\bar{\mathbf{p}}_i - \bar{\mathbf{p}}_j\|^2}{2\alpha_i^2}\right] \times \exp\left[-\frac{D(\bar{\mathbf{c}}_i, \bar{\mathbf{c}}_j)}{2\beta_i^2}\right] \times \prod_{k=1}^{K} \exp\left[-\frac{D_k(\bar{\mathbf{f}}_{i,k}, \bar{\mathbf{f}}_{j,k})}{2\gamma_{k,i}^2}\right],$$

Pixel screen coordinates

Mean sample color value

Scene features



(a) Screen position **(b)** Random parameters **(c)** World space coords. **(d)** Surface normals **(e)** Texture value **(f)** Sample color

Our result with a cross-bilateral filter (4 spp)

Overview on Convolutional Neural Networks (CNNs)

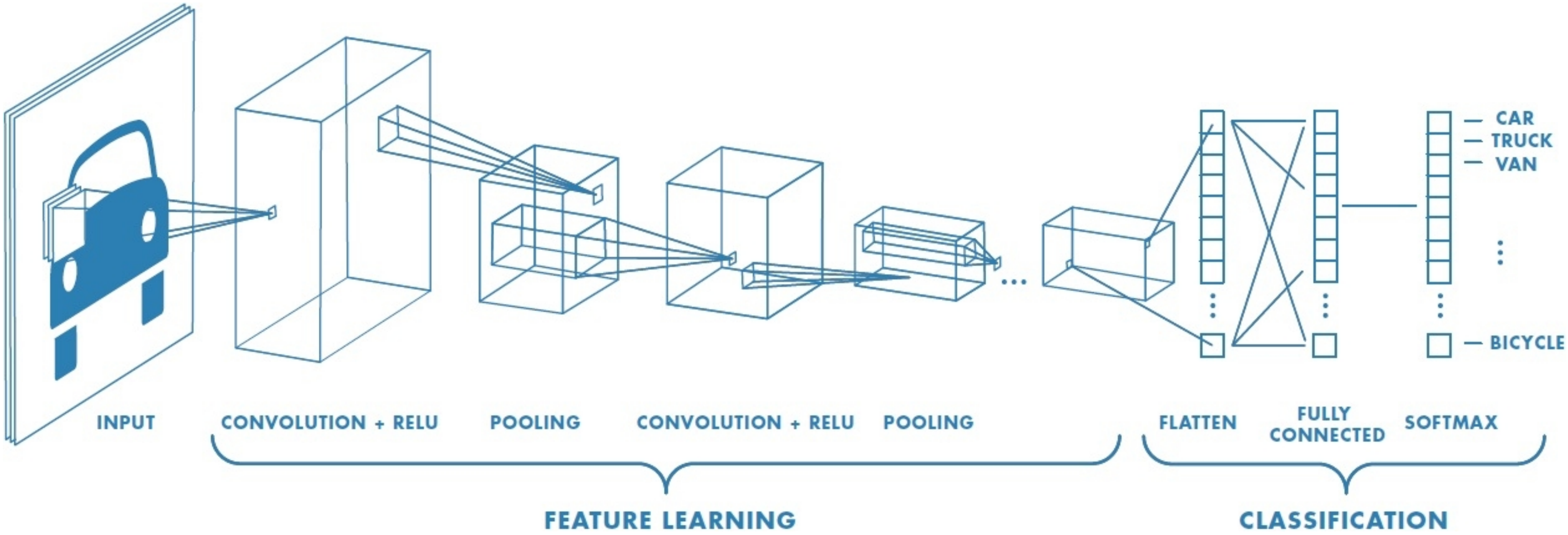
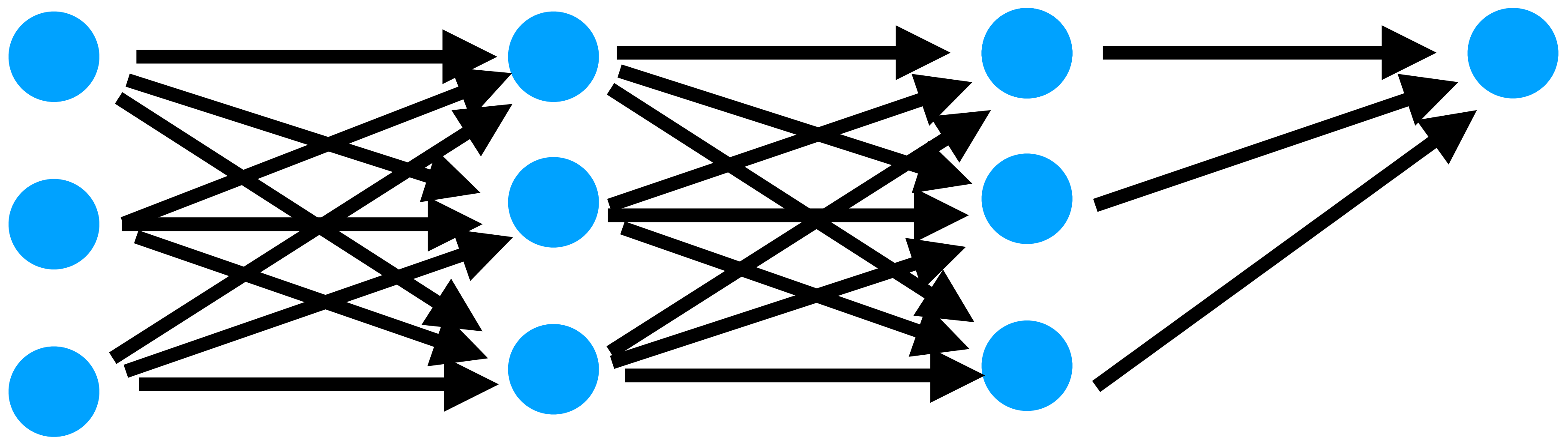
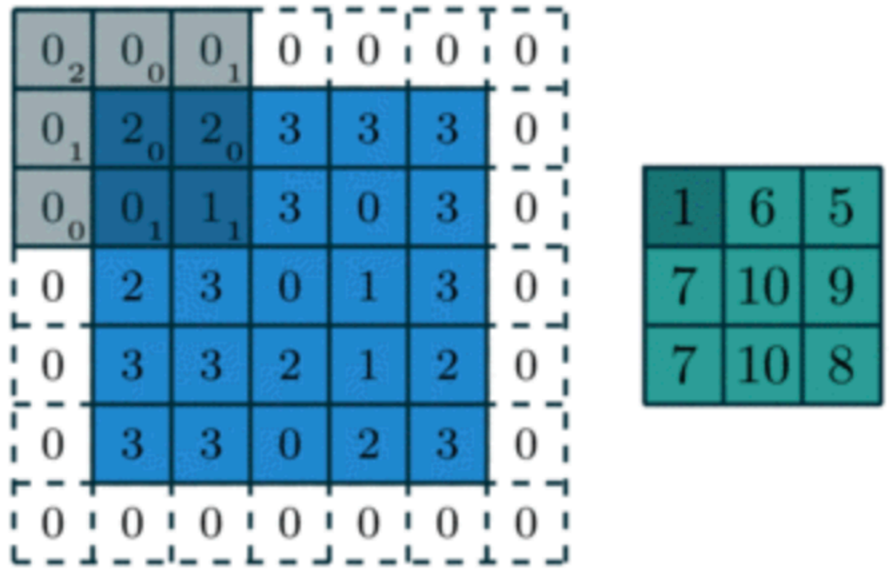
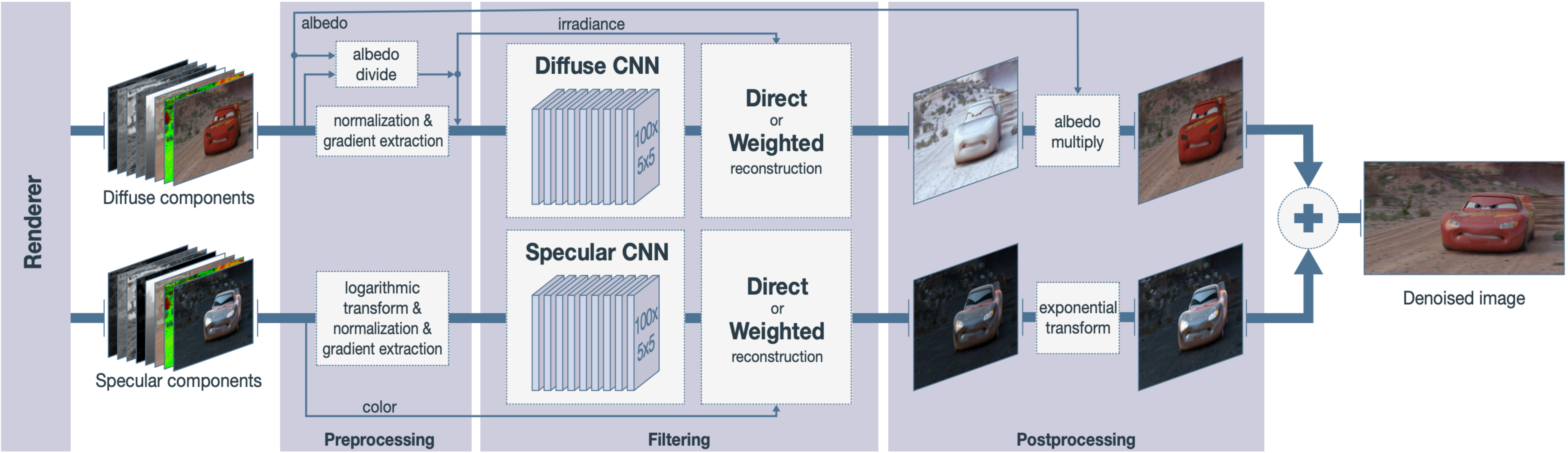


Image Courtesy: Mathworks (online tutorial)

Multi-layer Perceptron vs. CNNs

Multi-layer perceptron	CNNs
	
All nodes are fully connected in all layers	Weights are shared across layers
In theory, should be able to achieve good quality results in small number of layers.	Requires significant number of layers to capture all the features (e.g. Deep CNNs)
Number of weights to be learnt are very high	Relatively small number of weights required

Kernel-Predicting Networks for Denoising Monte-Carlo Renderings



Recurrent AutoEncoder for Interactive Reconstruction

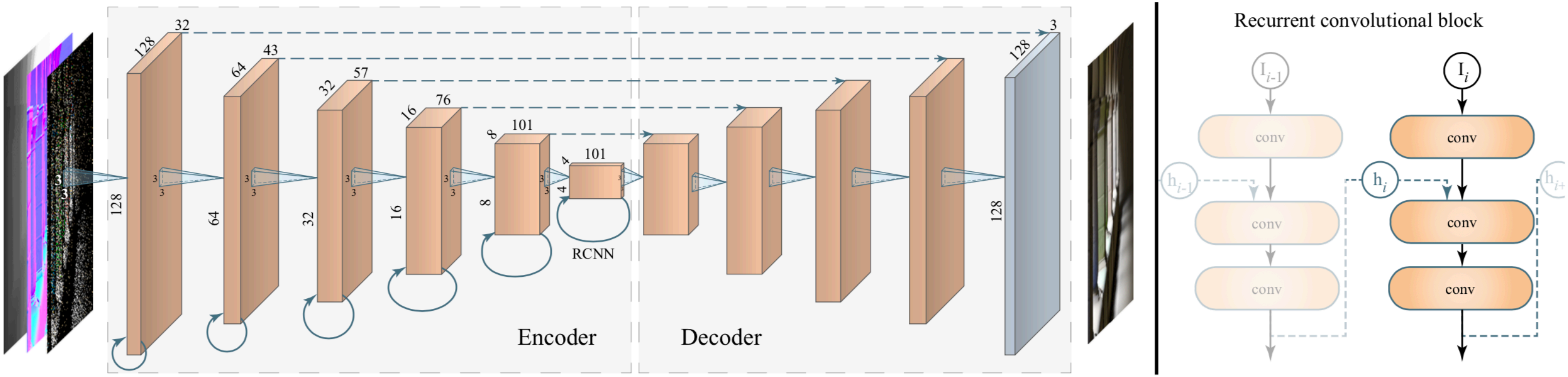
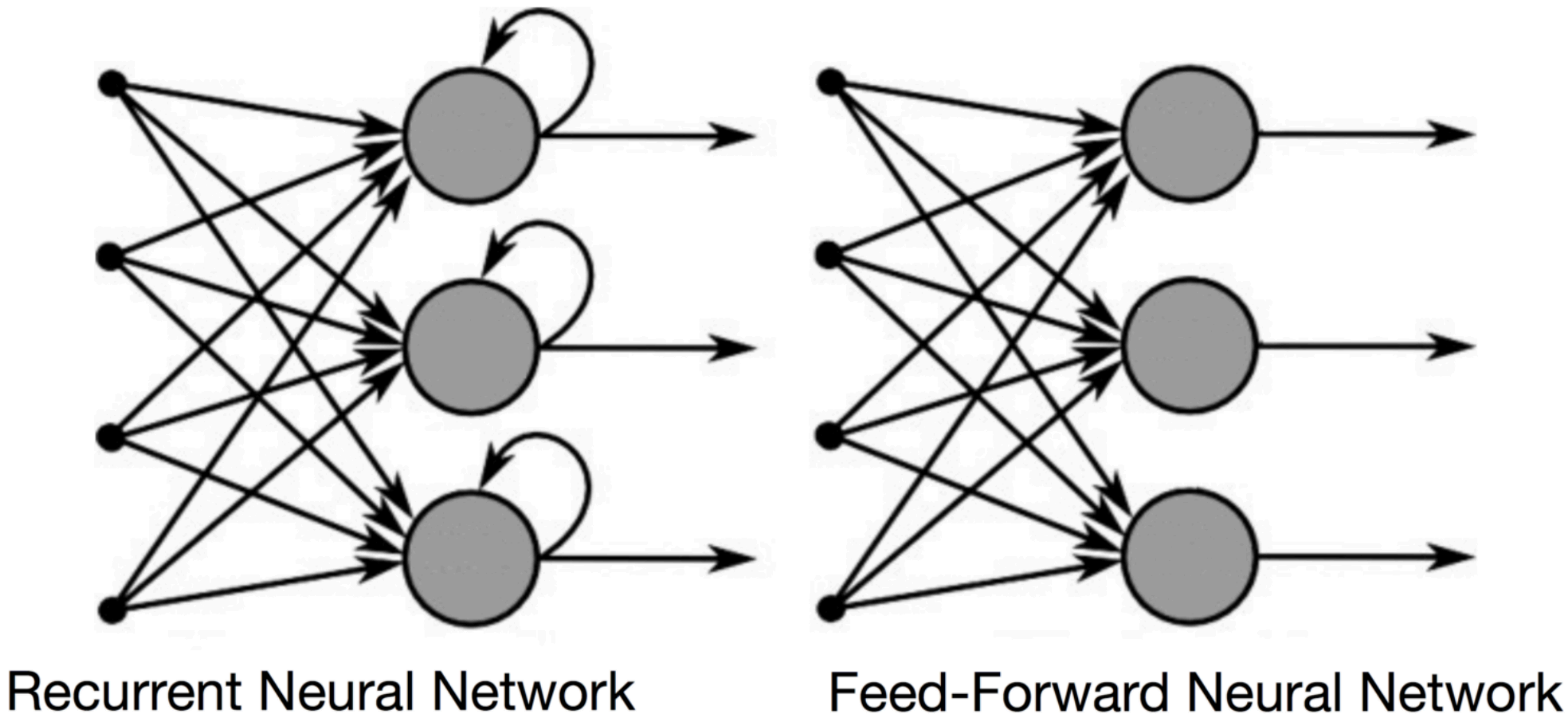


Fig. 2. Architecture of our recurrent autoencoder. The input is 7 scalar values per pixel (noisy RGB, normal vector, depth, roughness). Each encoder stage has a convolution and 2×2 max pooling. A decoder stage applies a 2×2 nearest neighbor upsampling, concatenates the per-pixel feature maps from a skip connection (the spatial resolutions agree), and applies two sets of convolution and pooling. All convolutions have a 3×3-pixel spatial support. On the right we visualize the internal structure of the recurrent RCNN connections. I is the new input and h refers to the hidden, recurrent state that persists between animation frames.

Recurrent Neural Networks vs. Simple Feed-Forward NN

[Source link](#)



Loss Functions

Spatial Loss to emphasize more the dark regions

$$L_s = \frac{1}{N}\sum_i^N |P_i - T_i|$$

Temporal loss

$$L_t = \frac{1}{N}\sum_i^N \left(\left| \frac{\partial P_i}{\partial t} - \frac{\partial T_i}{\partial t} \right| \right)$$

High frequency error norm loss for stable edges

$$L_g = \frac{1}{N}\sum_i^N |\nabla P_i - \nabla T_i|$$

Final Loss is a weighted averaged of above losses

$$L = w_s L_s + w_g L_g + w_t L_t$$

Pixel-space Kernel Predicting Denoising

#Learnable Parameters?

How to compute "learnable" parameters?

Sample-based MC Denoising

How to compute "learnable" parameters?

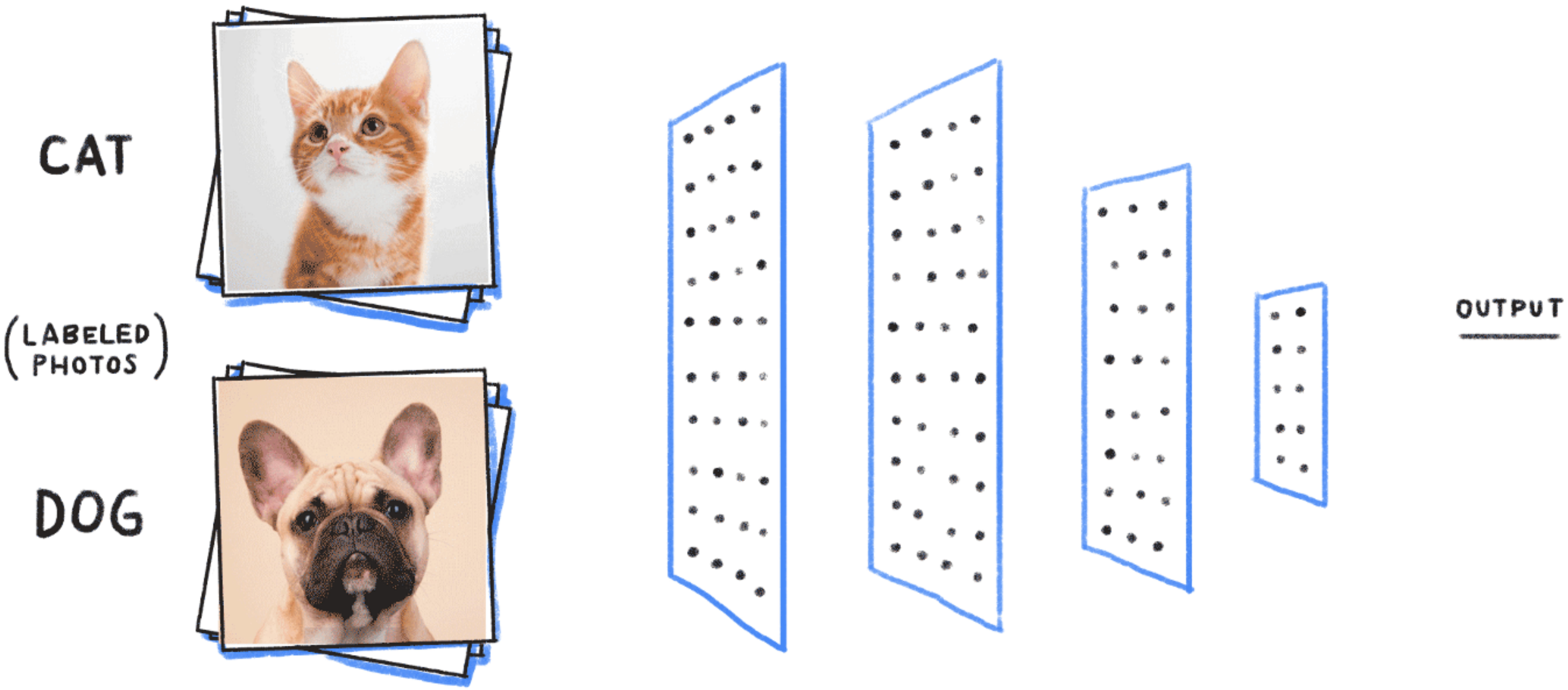


Image Source: Google

How to compute "learnable" parameters?

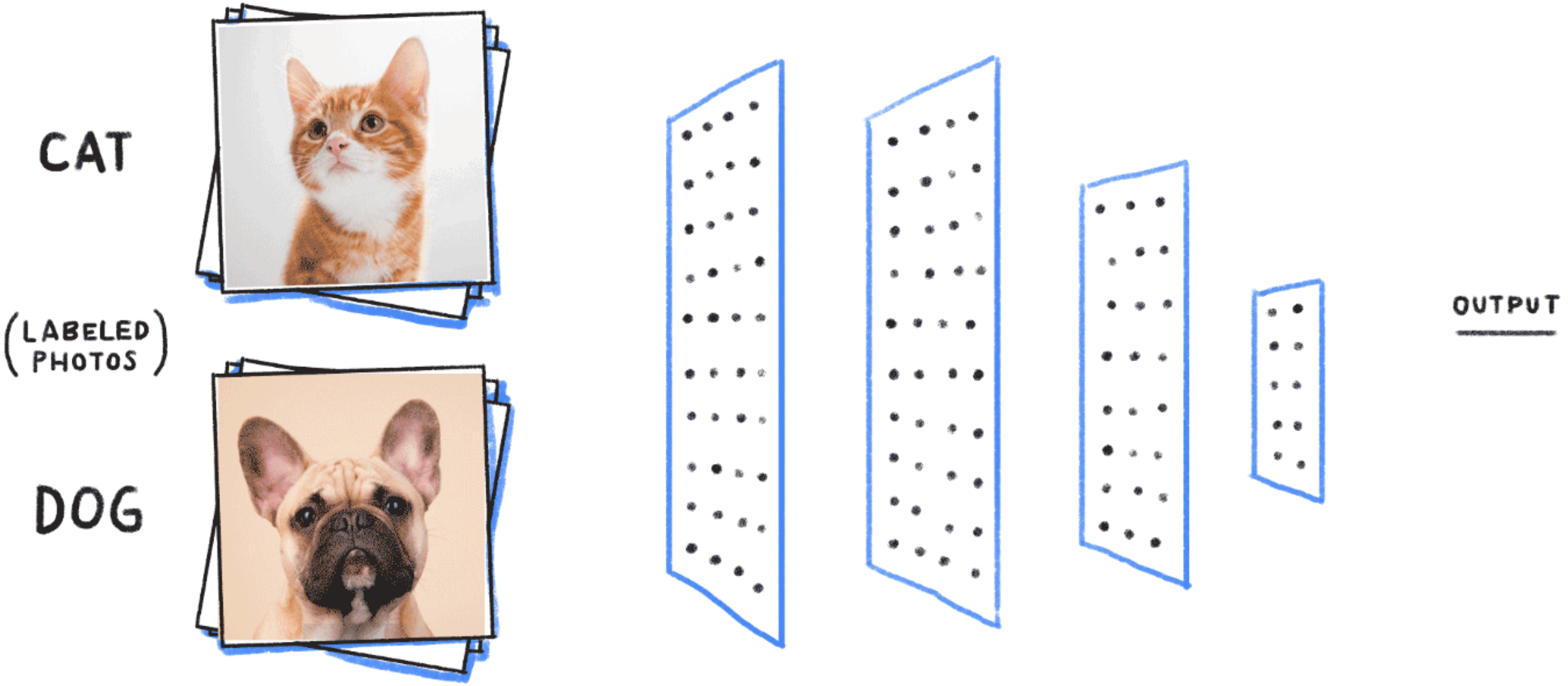


Image Source: Google

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Feed-Forward Neural Network

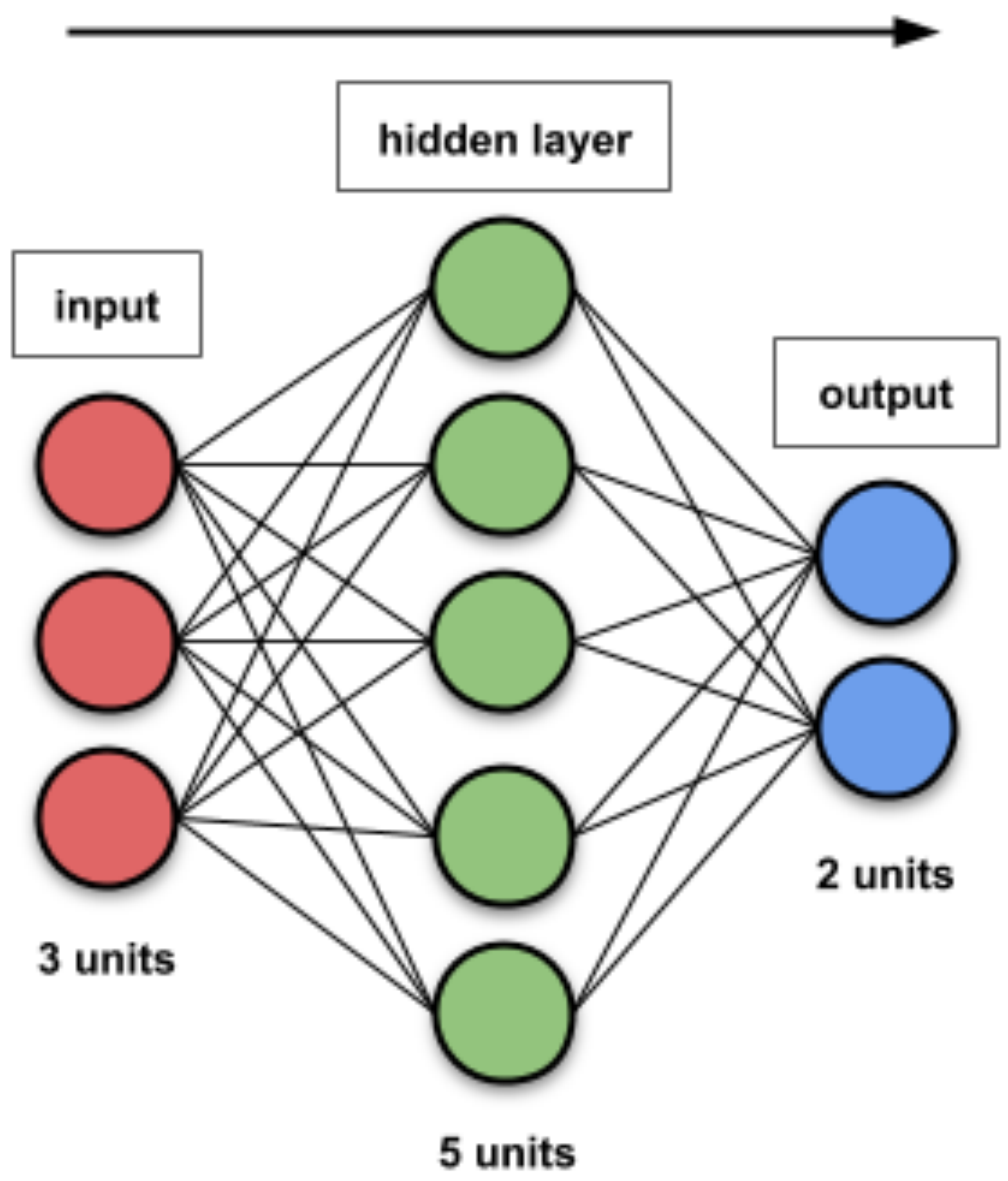
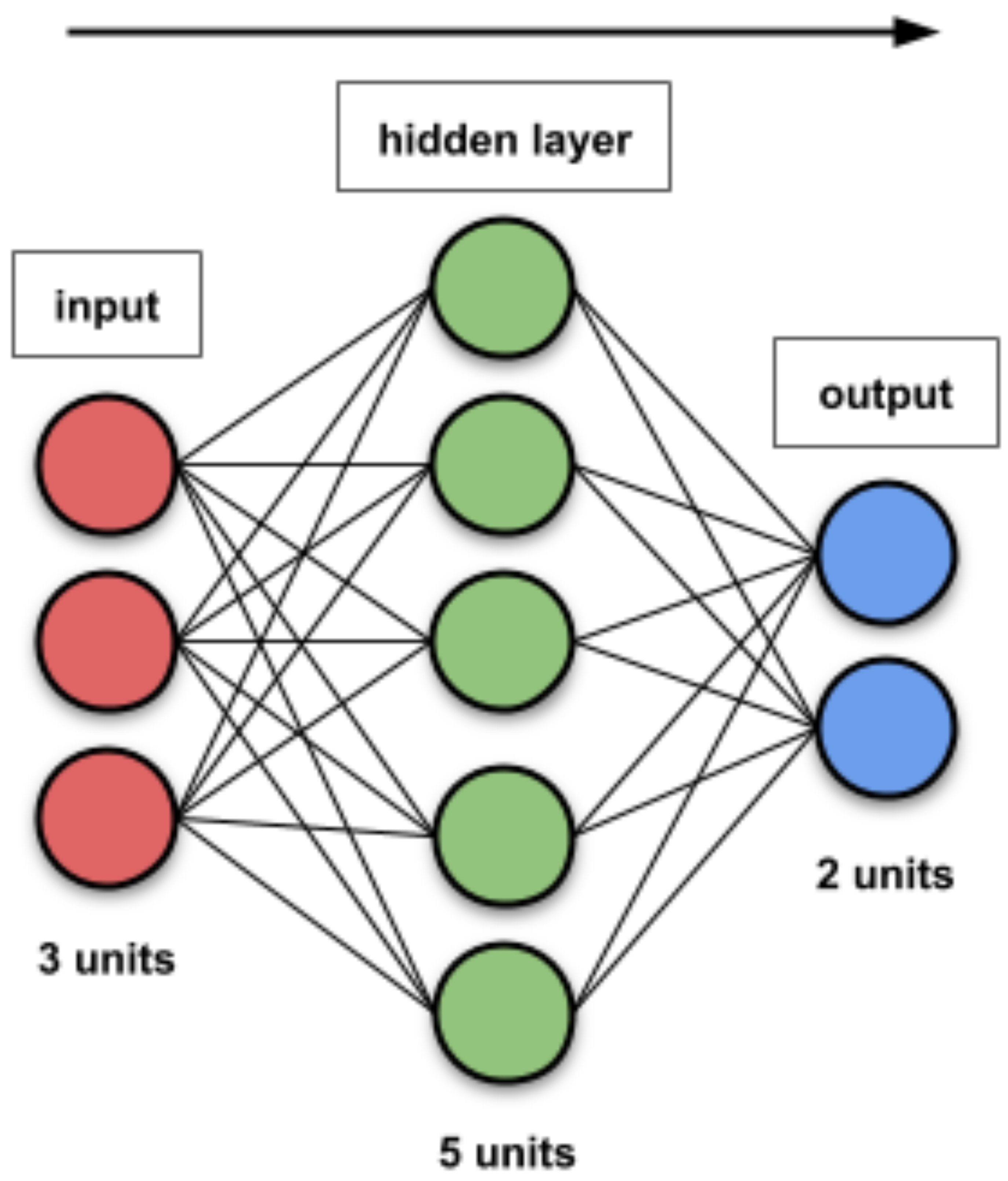


Image Source: towards-data-science

Feed-Forward Neural Network



(3 x 5) + (5 x 2) + (5 + 2) = 17 parameters

weights biases

Image Source: towards-data-science

Feed-Forward Neural Network

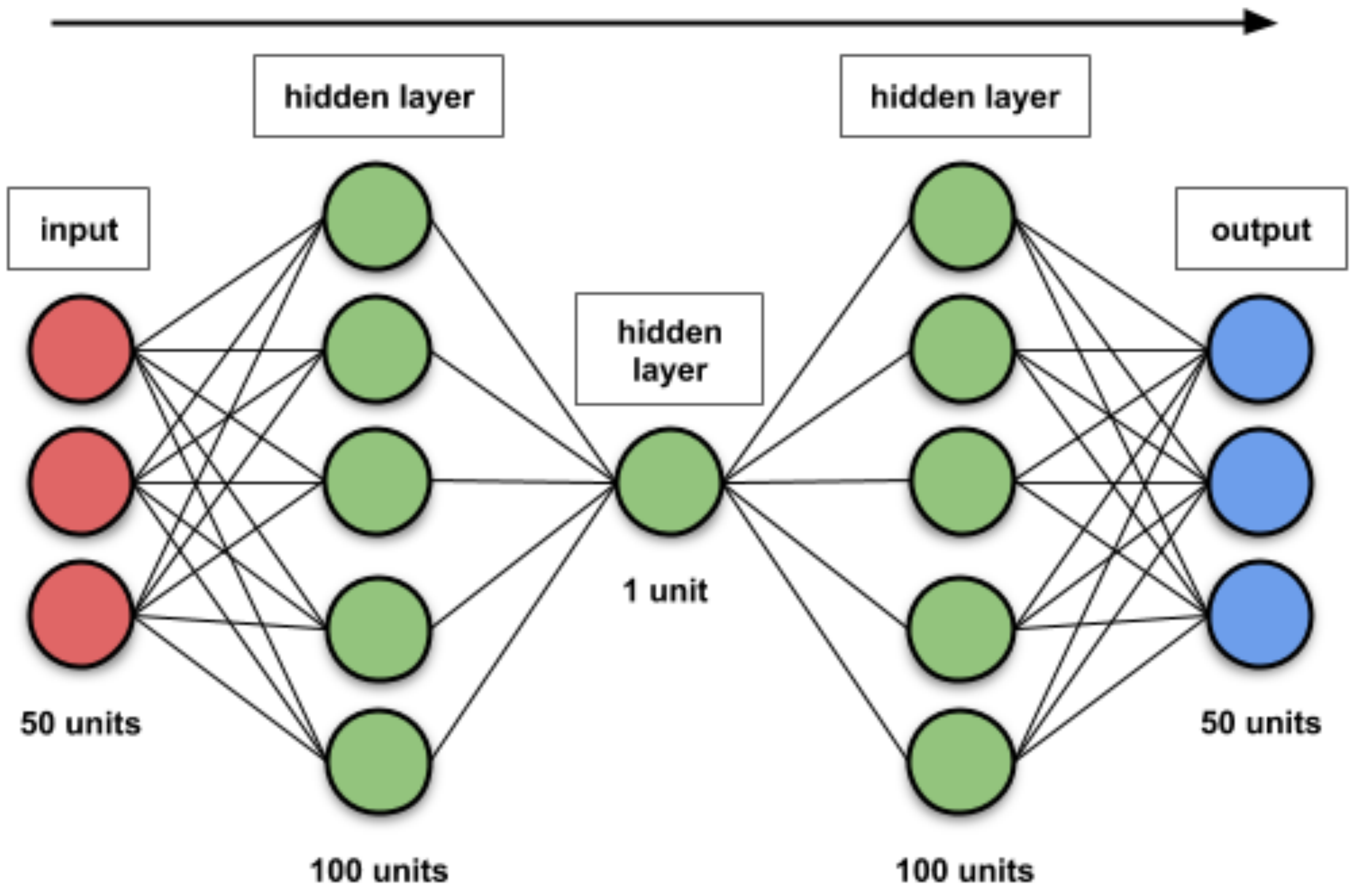


Image Source: towards-data-science

Pixel-space
Kernel Predicting
Denoising

#Learnable
Parameters?

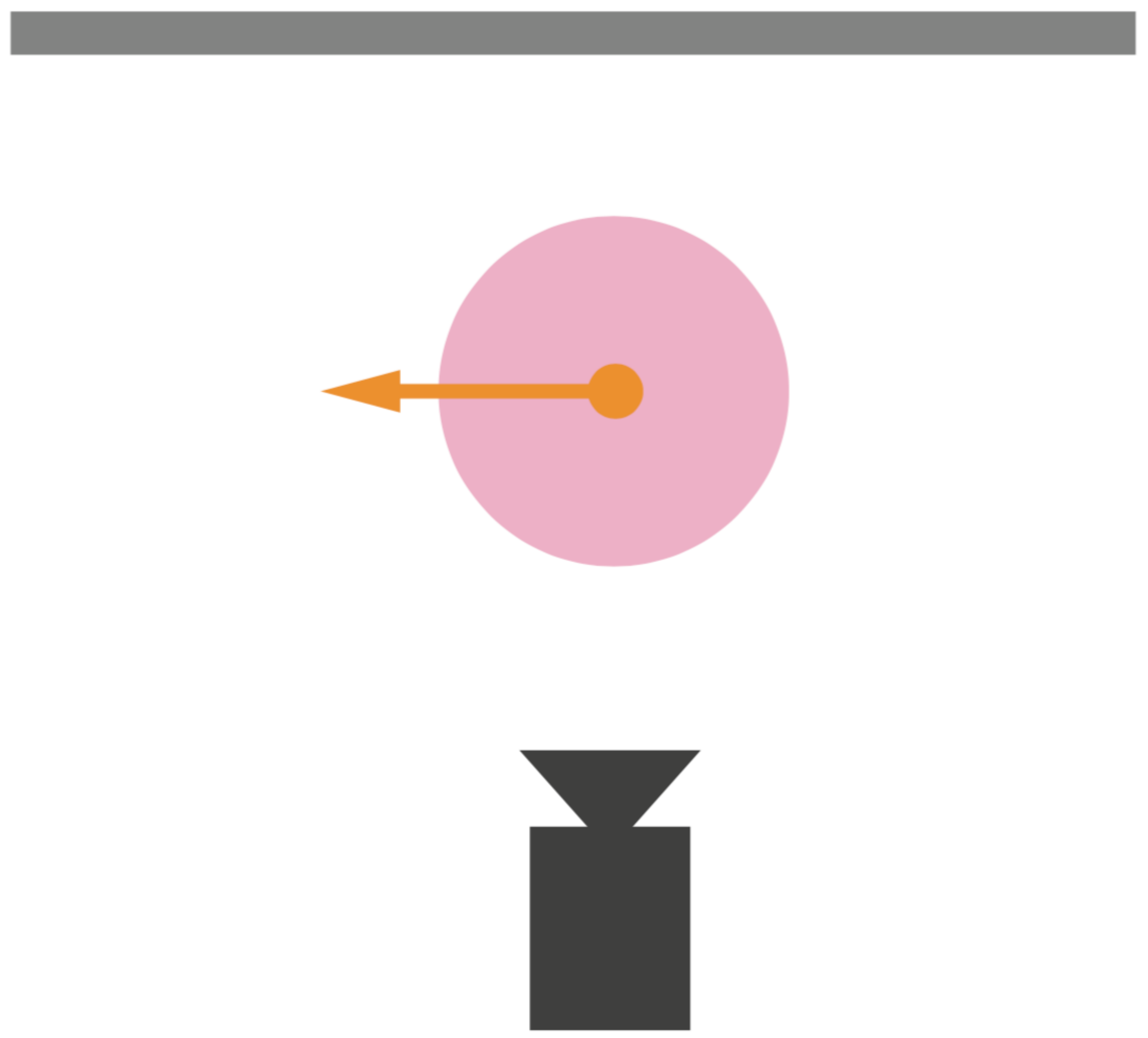
Sample-based
MC Denoising

Sample-based Denoising Network

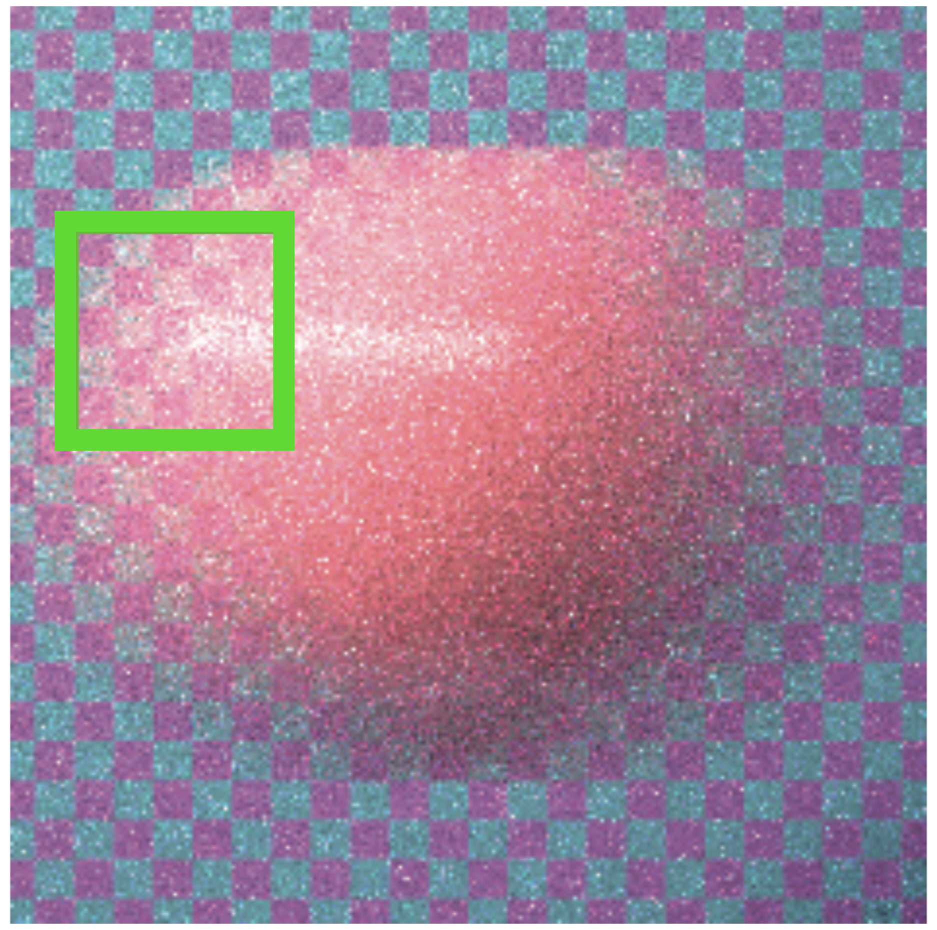
Michael Gharbi, Tzu-Mao Li, Miika Aittala, Jakko Lehtinen, Fredo Durand

SIGGRAPH 2019

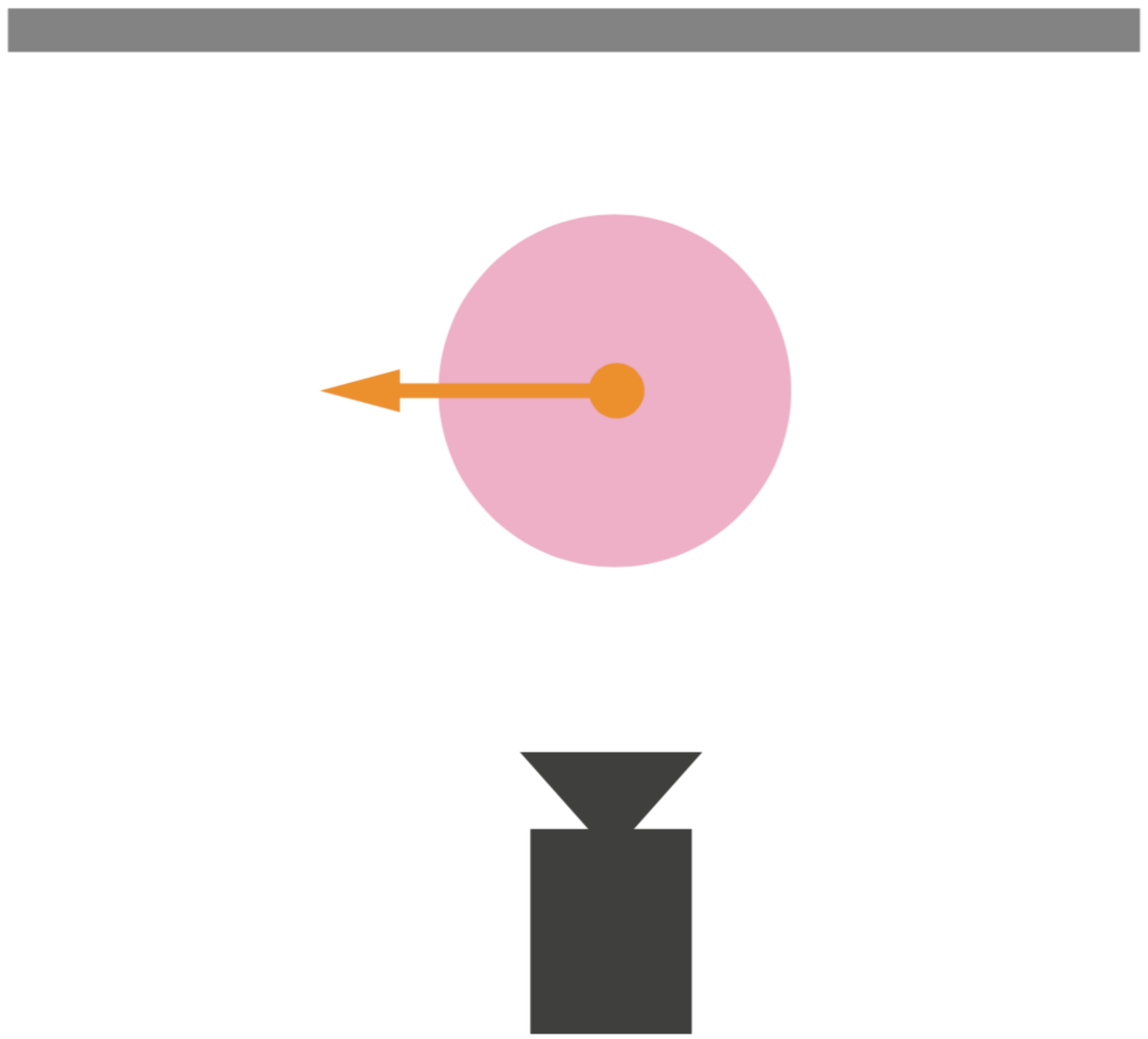
Multimodal distribution of sample features



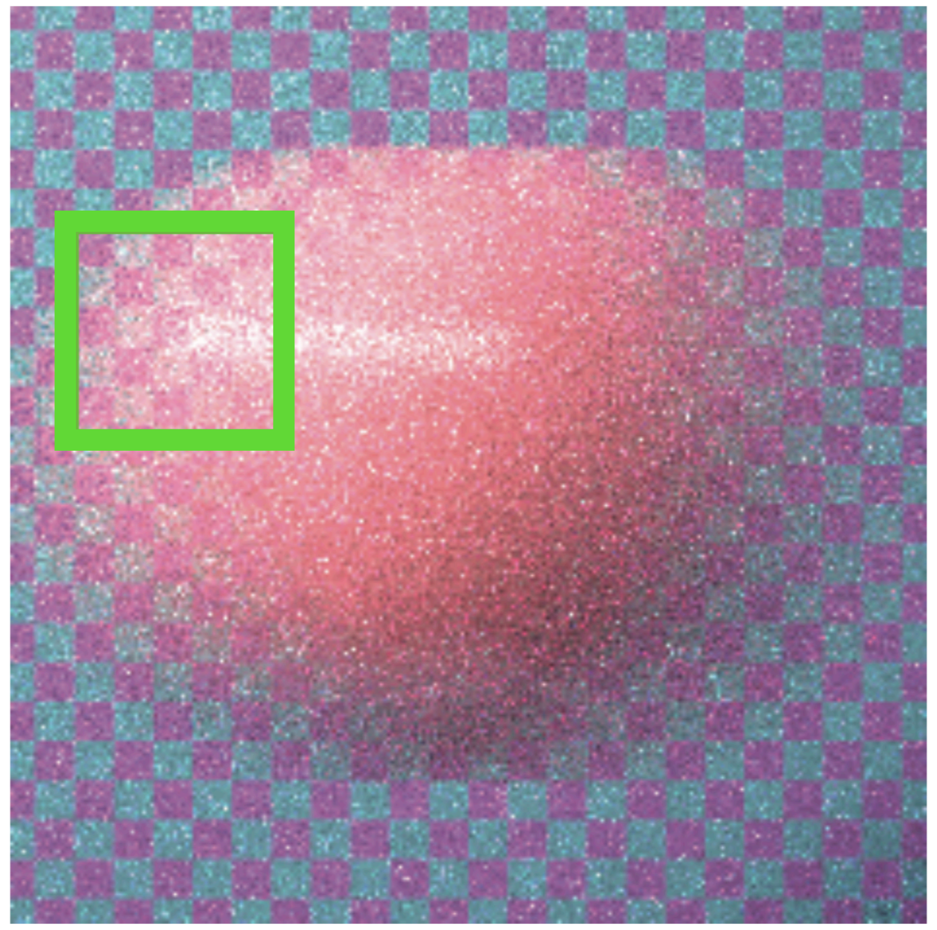
Input 16spp

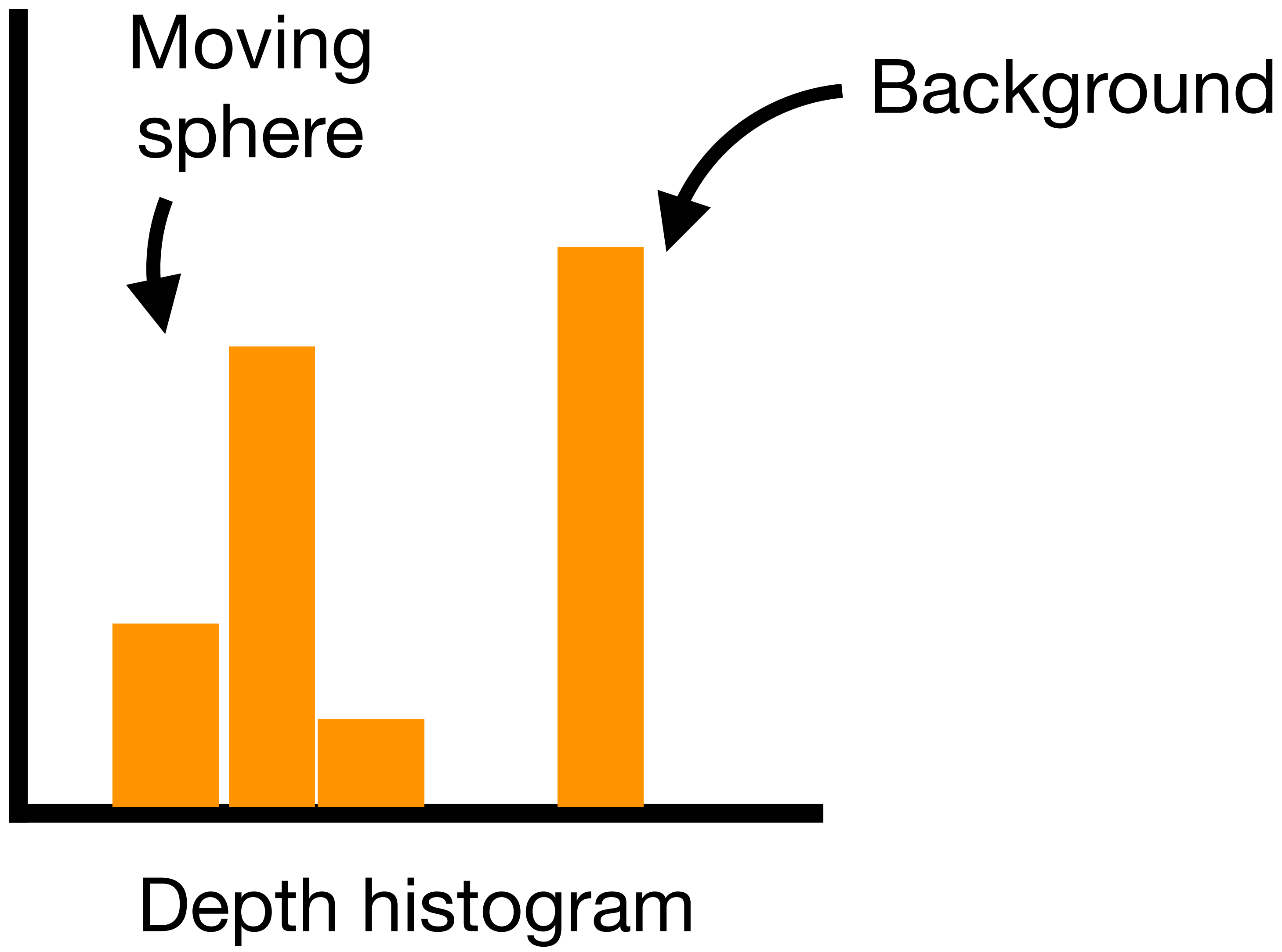


Multimodal distribution of sample features

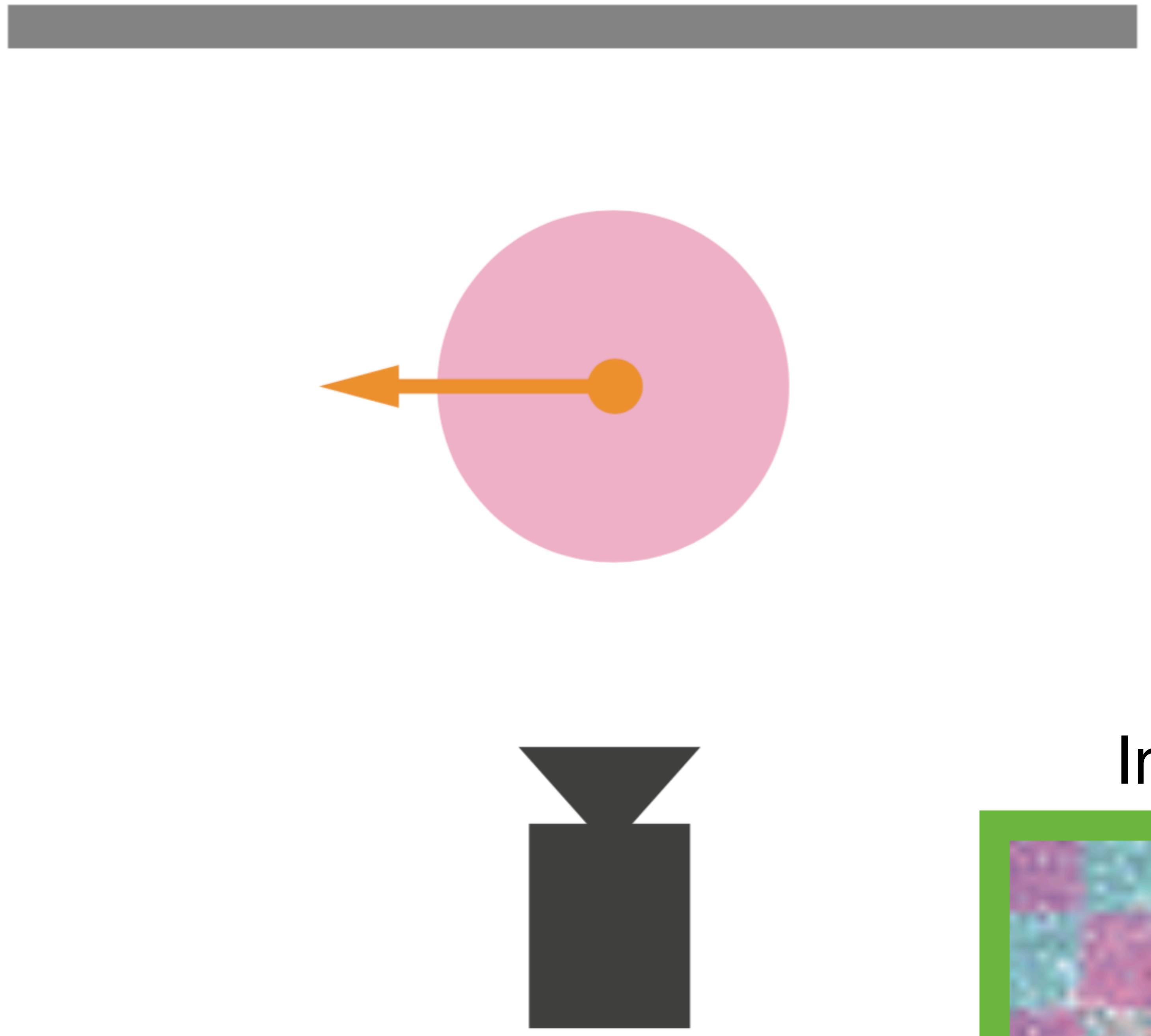


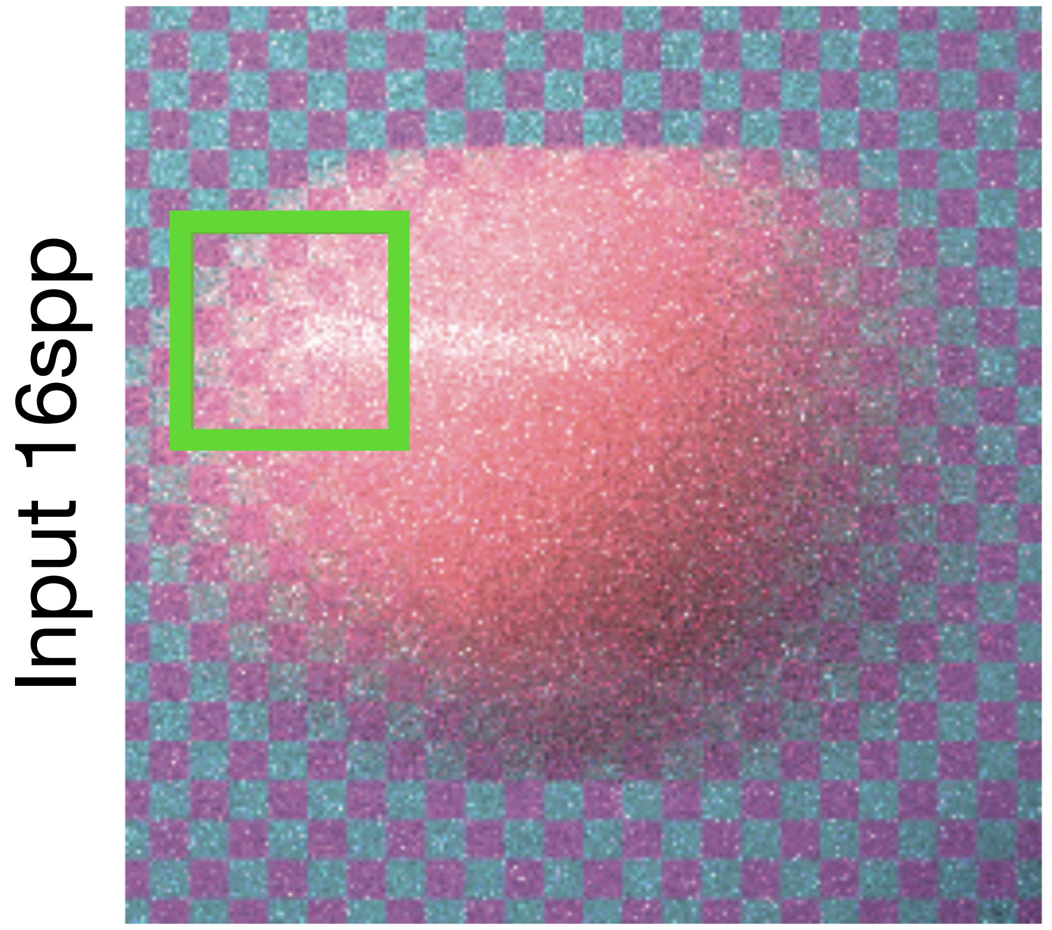
Input 16spp

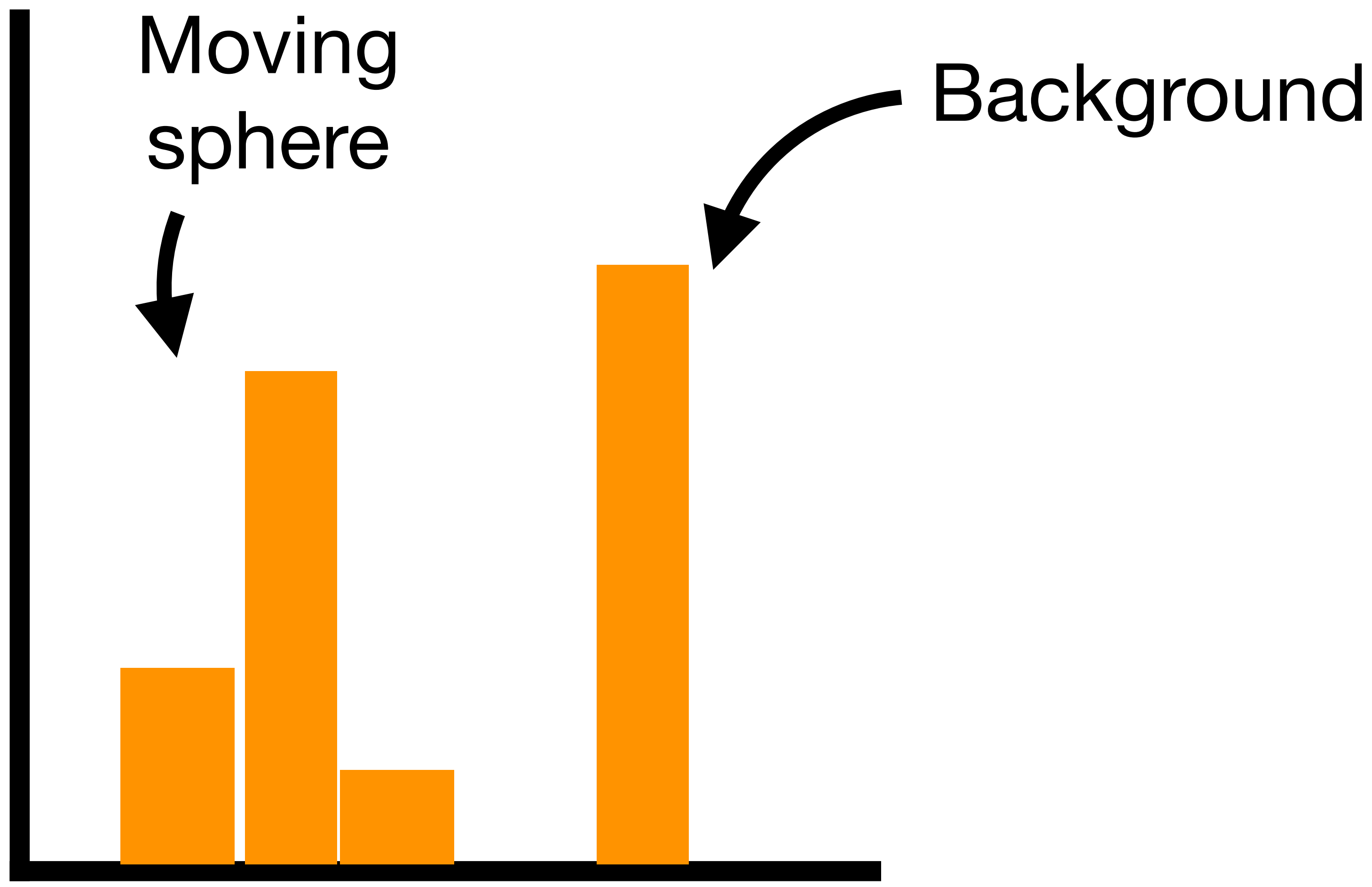




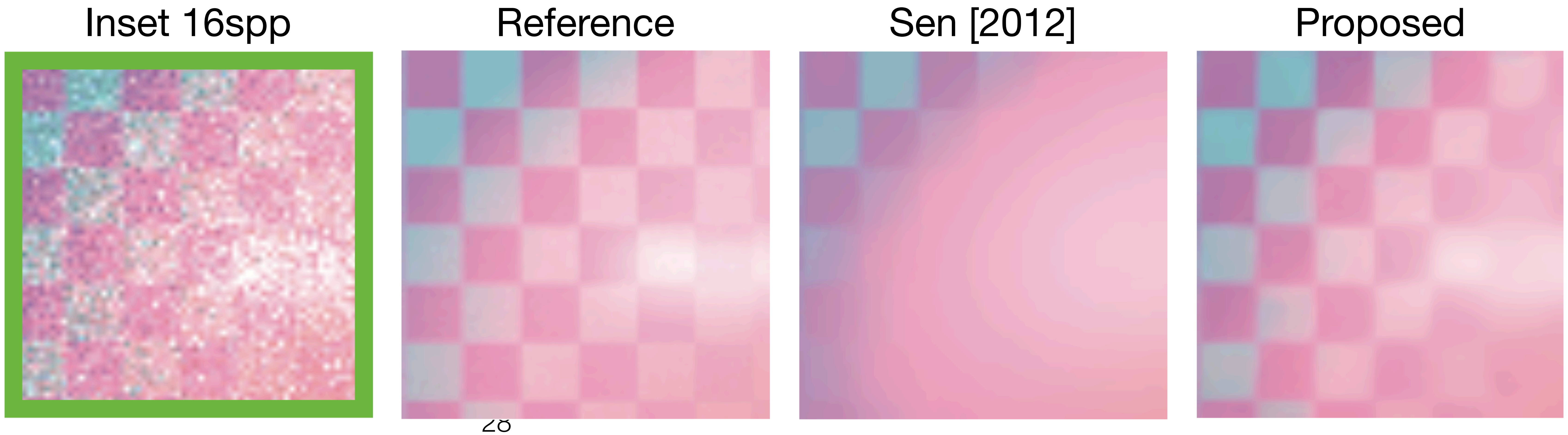
Multimodal distribution of sample features



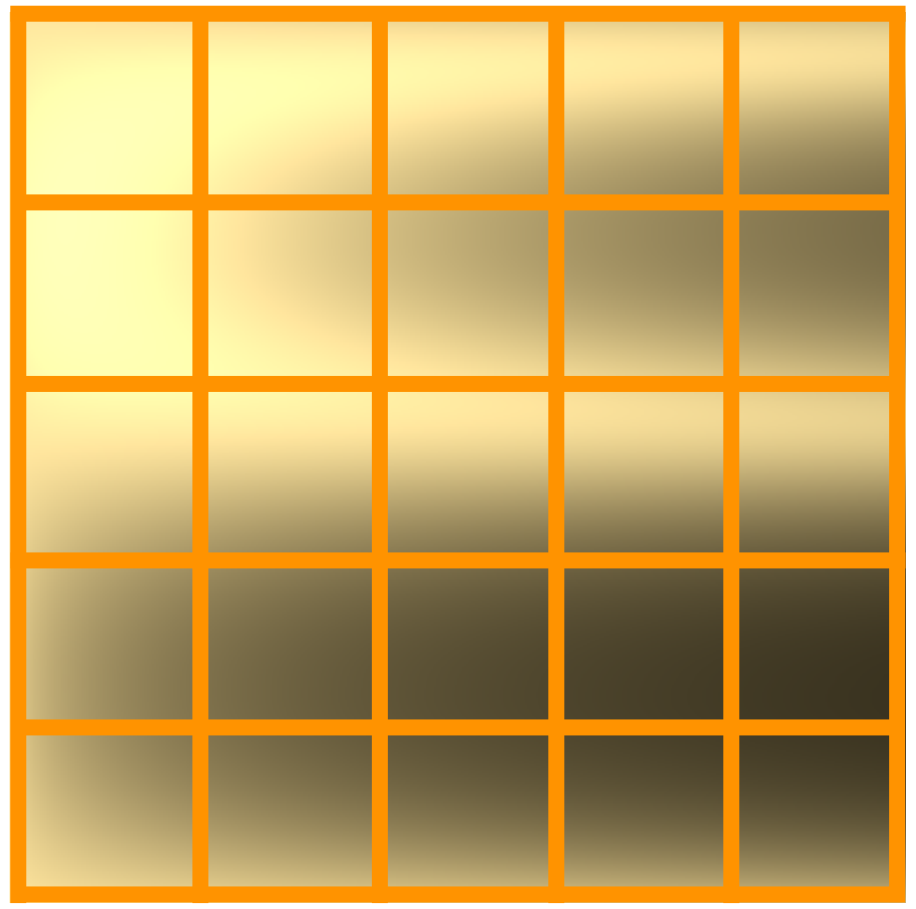




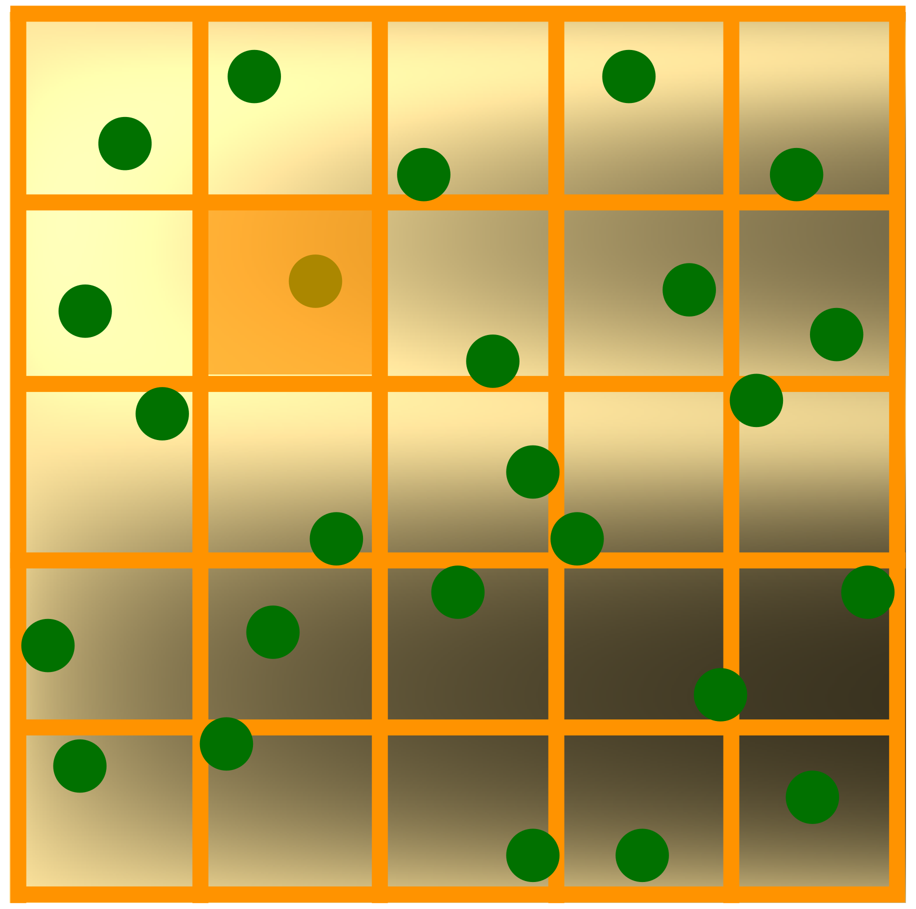
Depth histogram



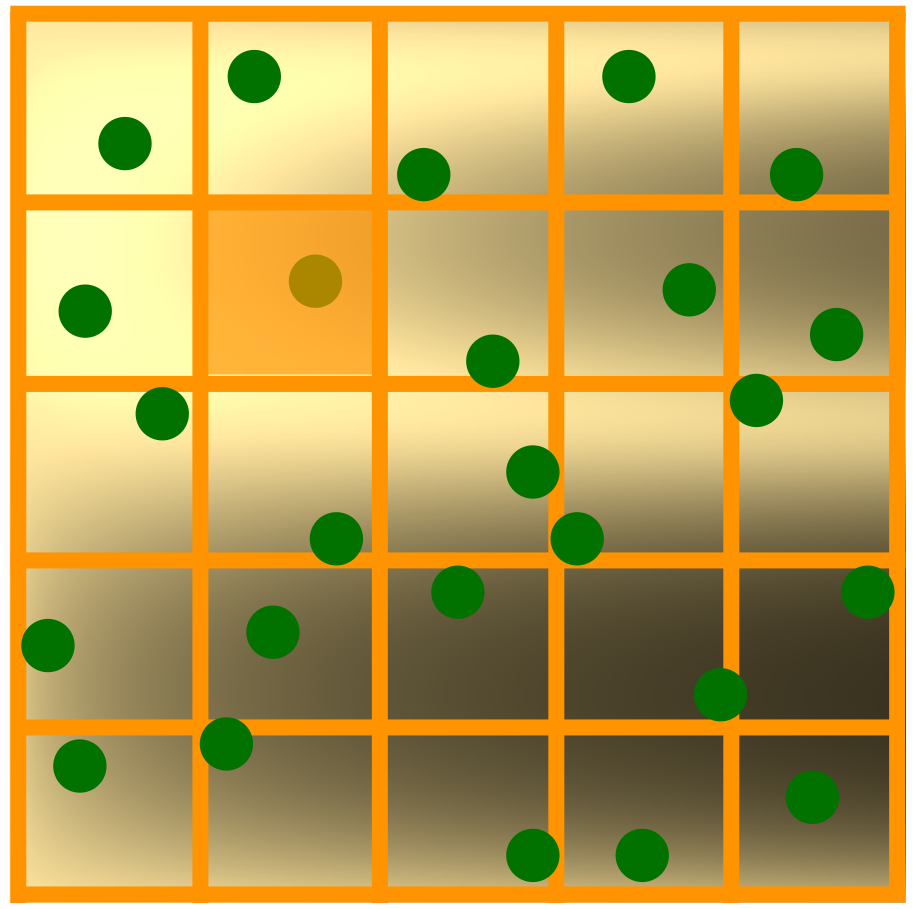
Reconstruction: Kernel Gather



Reconstruction: Kernel Gather



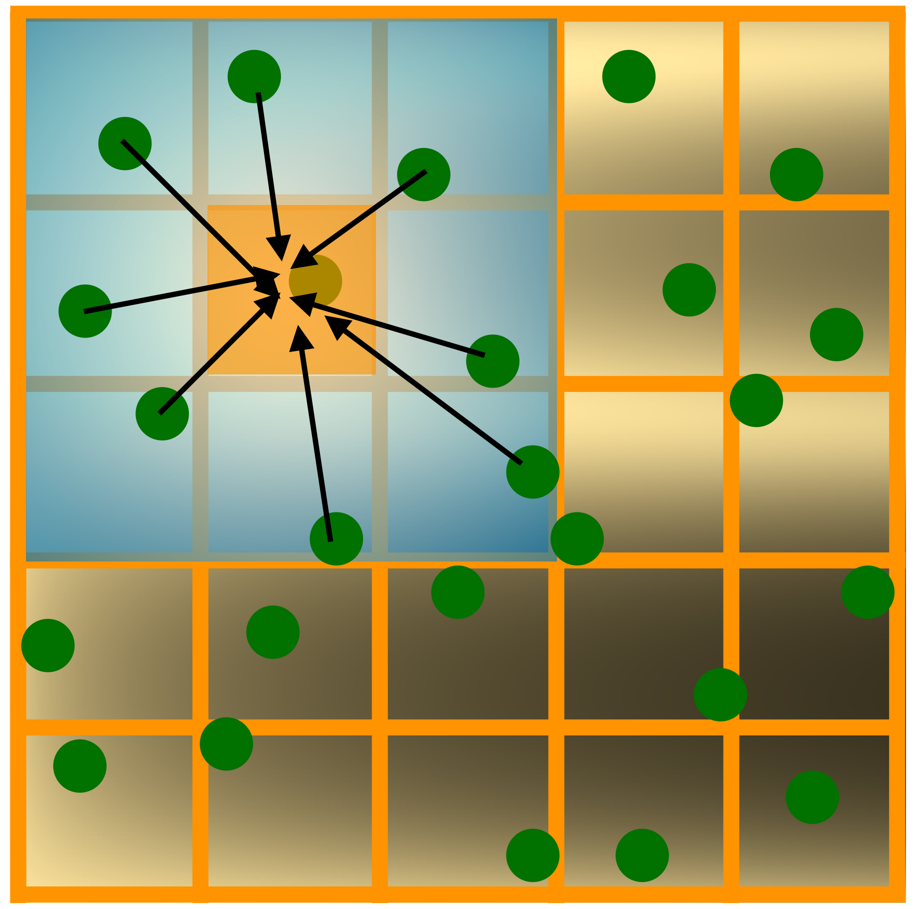
Reconstruction: Kernel Gather



Kernel

Reconstruction: Kernel Gather

Kernel gather

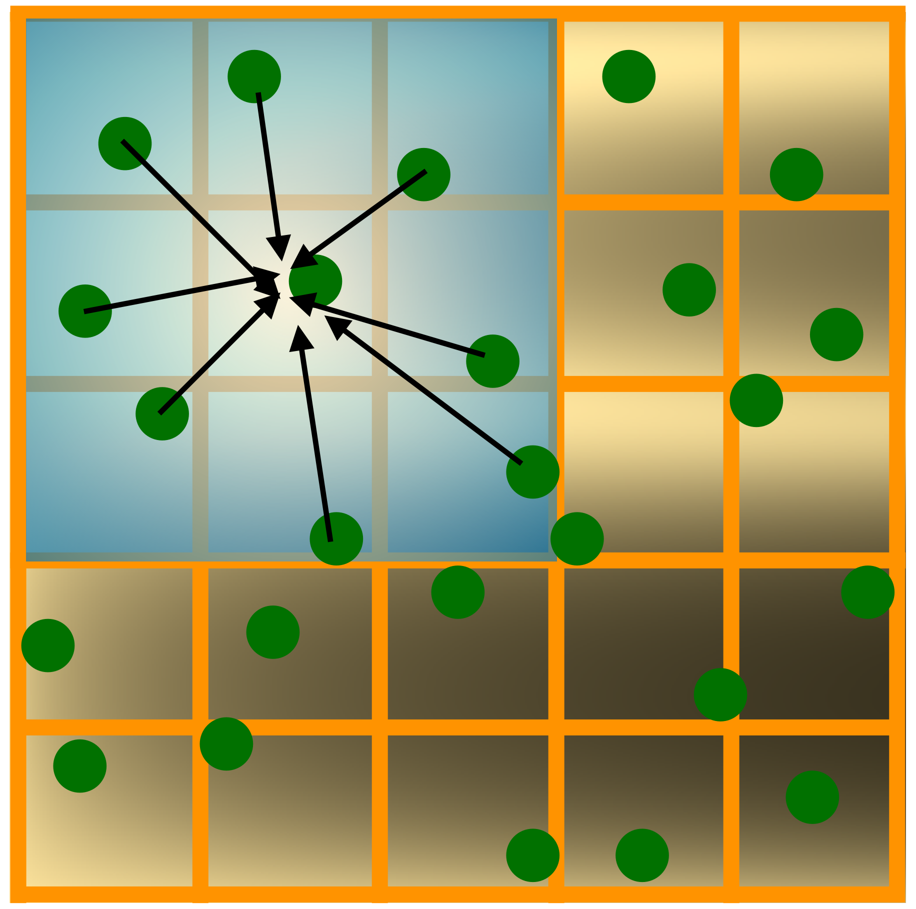


2D example

How should nearby samples influence me?

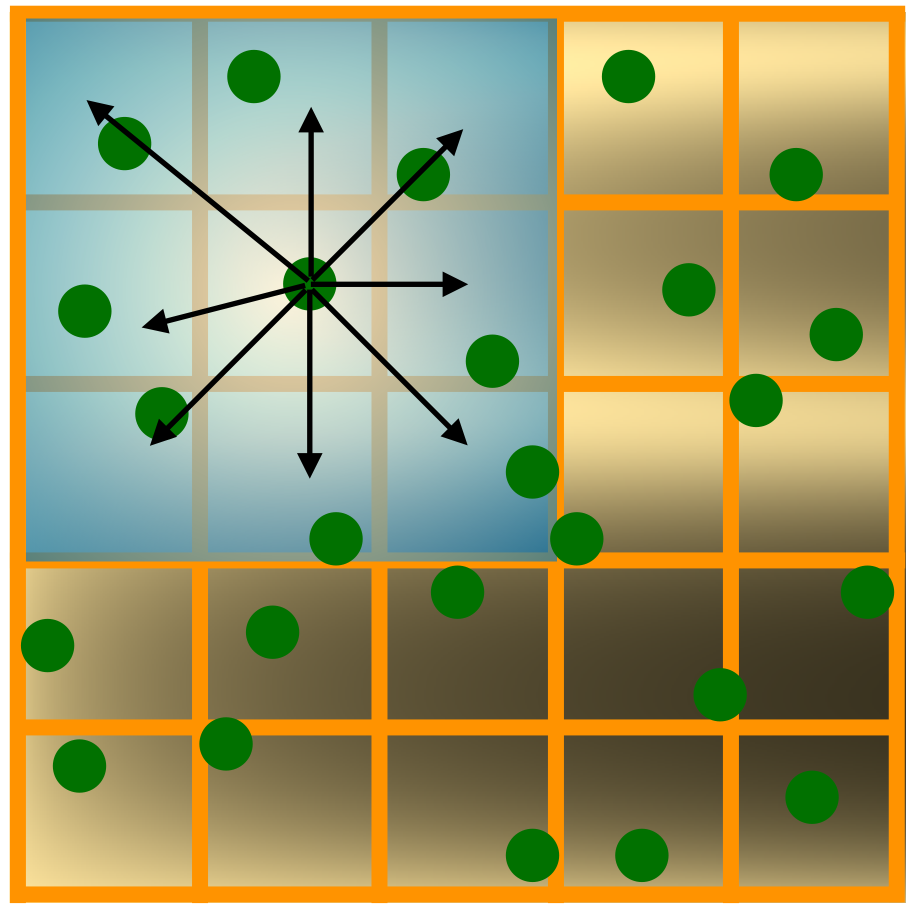
Reconstruction: Kernel Splatting

Kernel gather



2D example

Kernel Splatting

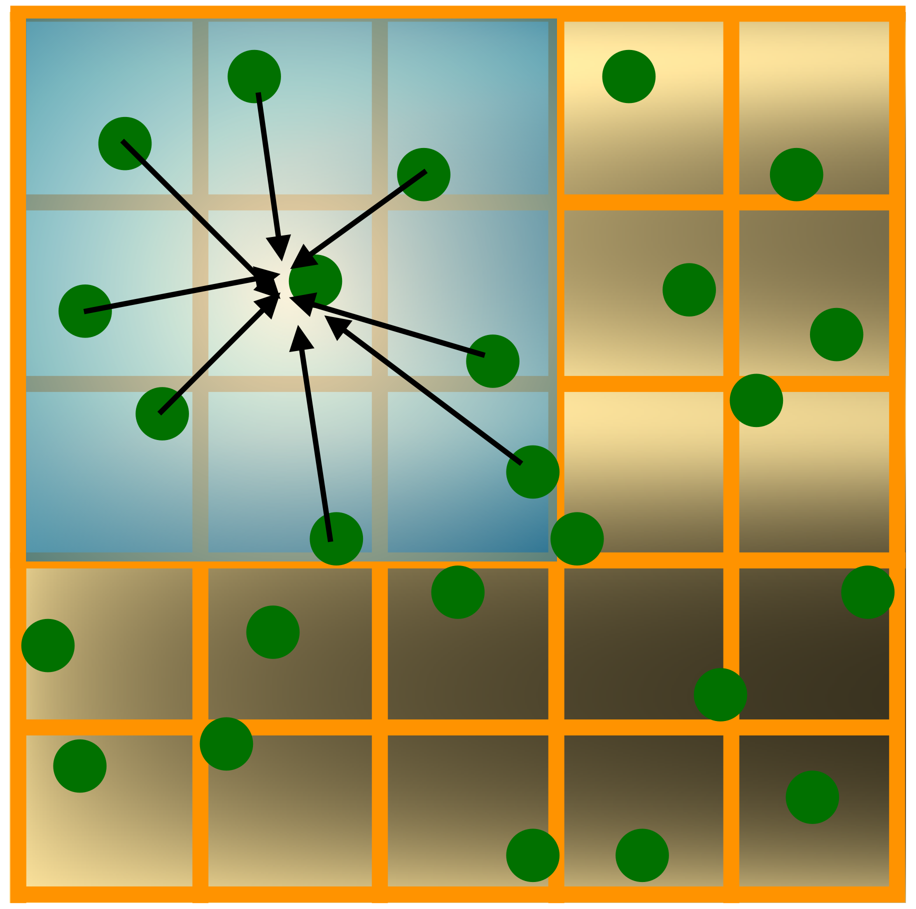


2D example

How should nearby samples influence me?

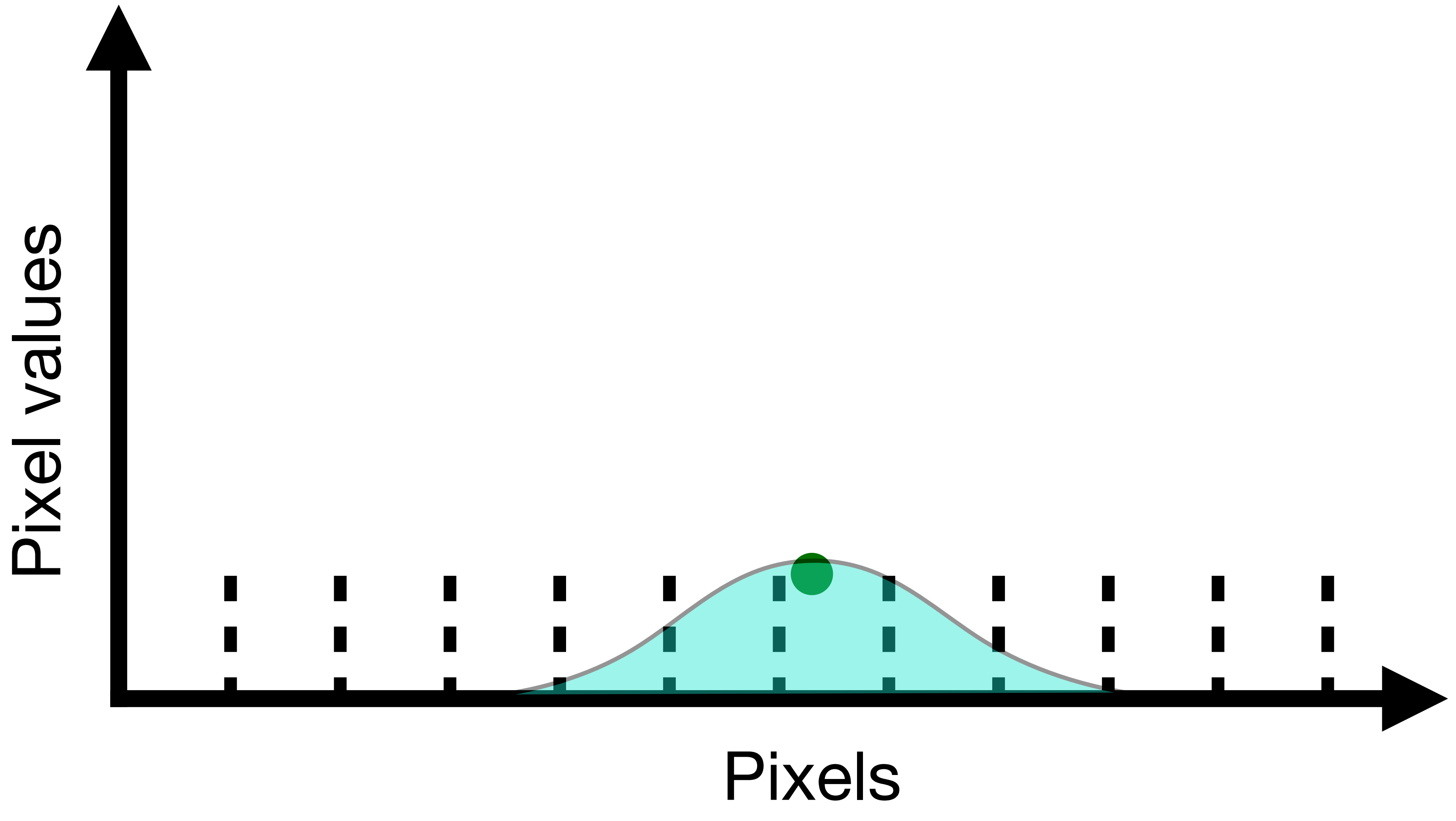
Reconstruction: Kernel Splatting

Kernel gather



2D example

Kernel Splatting

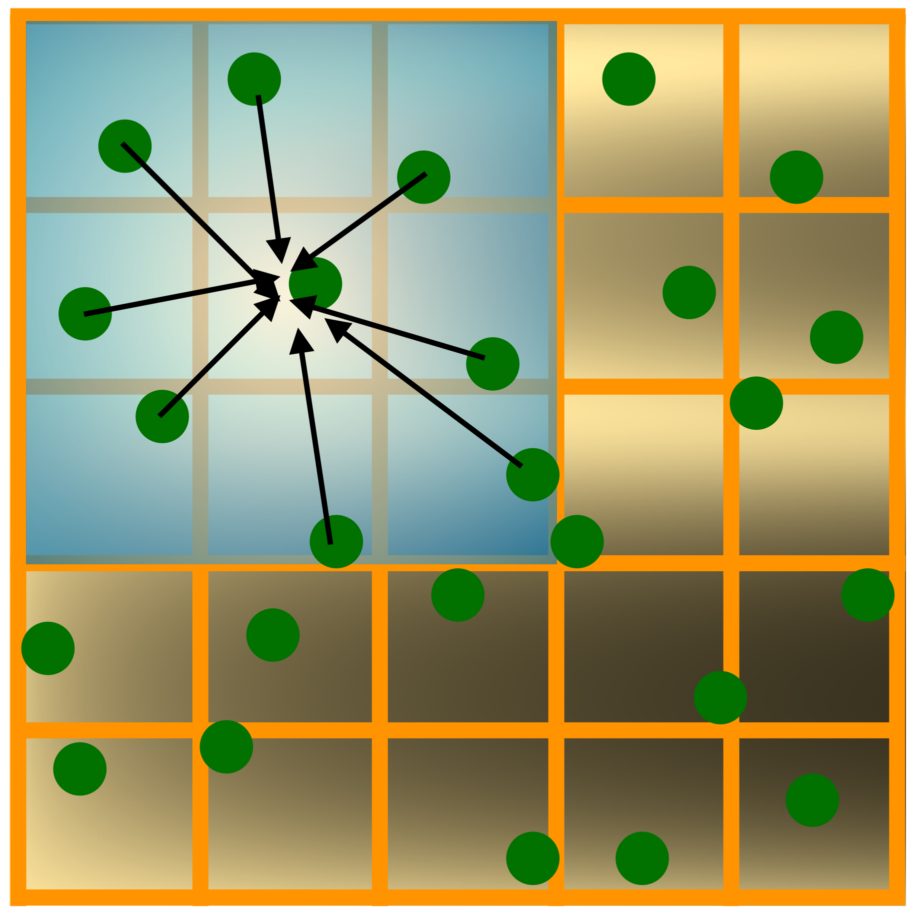


1D example

How should nearby samples influence me?

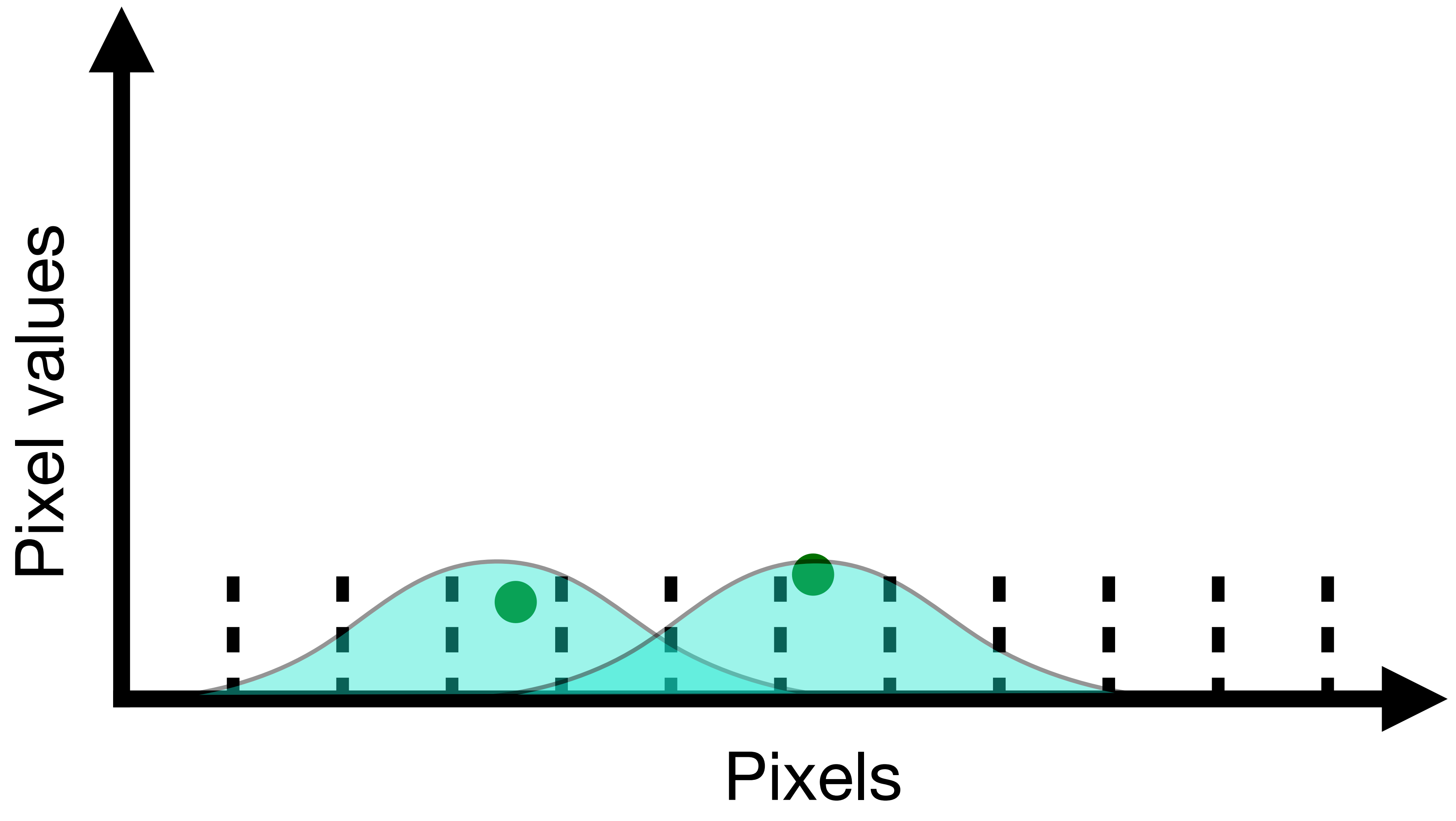
Reconstruction: Kernel Splatting

Kernel gather



2D example

Kernel Splatting

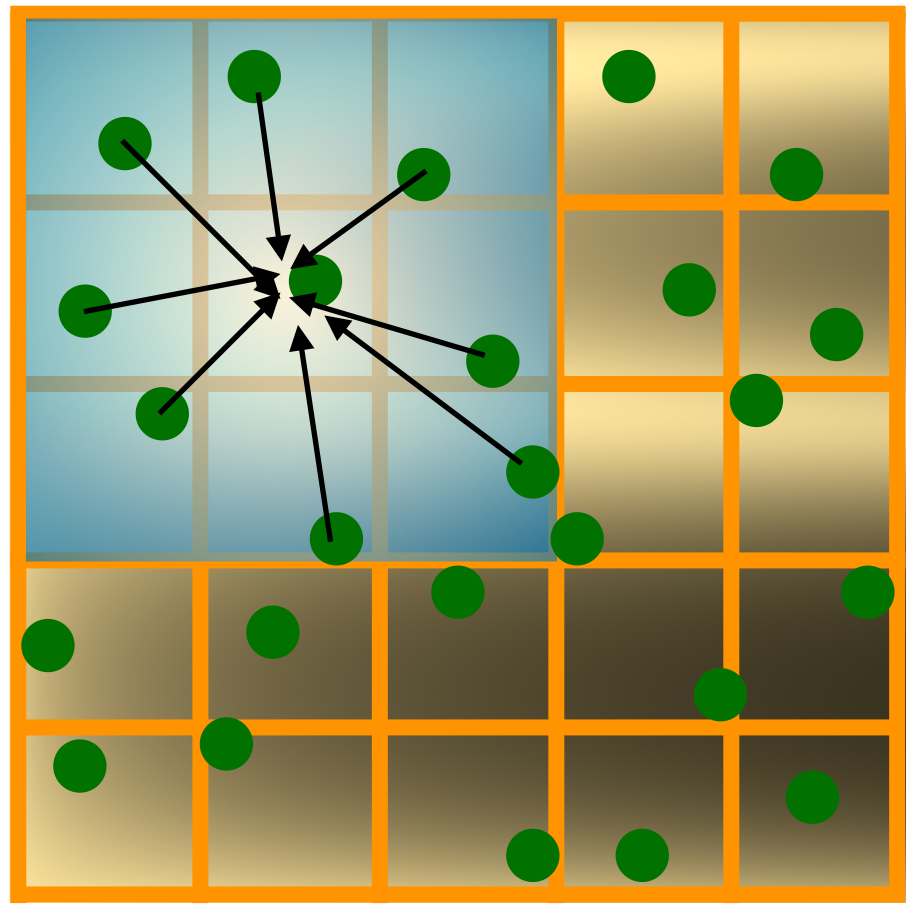


1D example

How should nearby samples influence me?

Reconstruction: Kernel Splatting

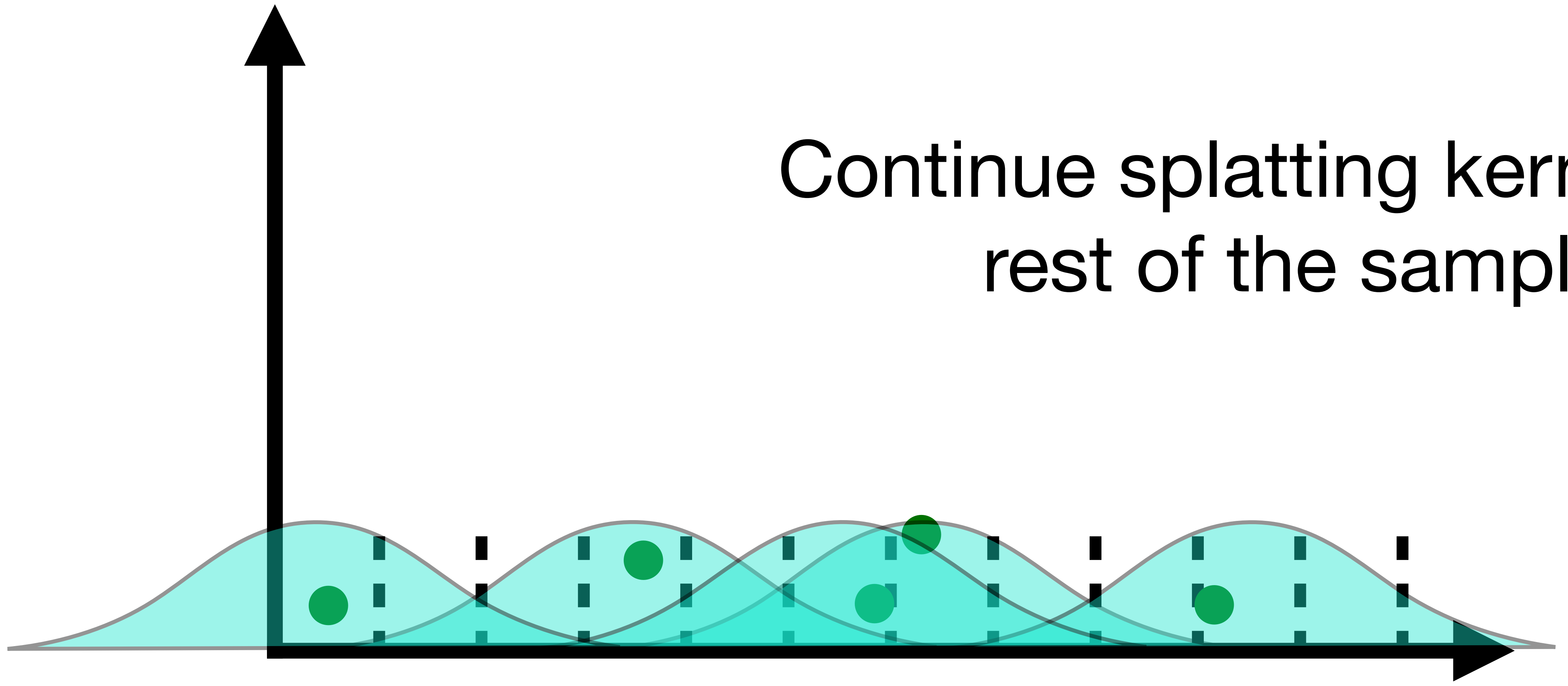
Kernel gather



2D example

How should nearby samples influence me?

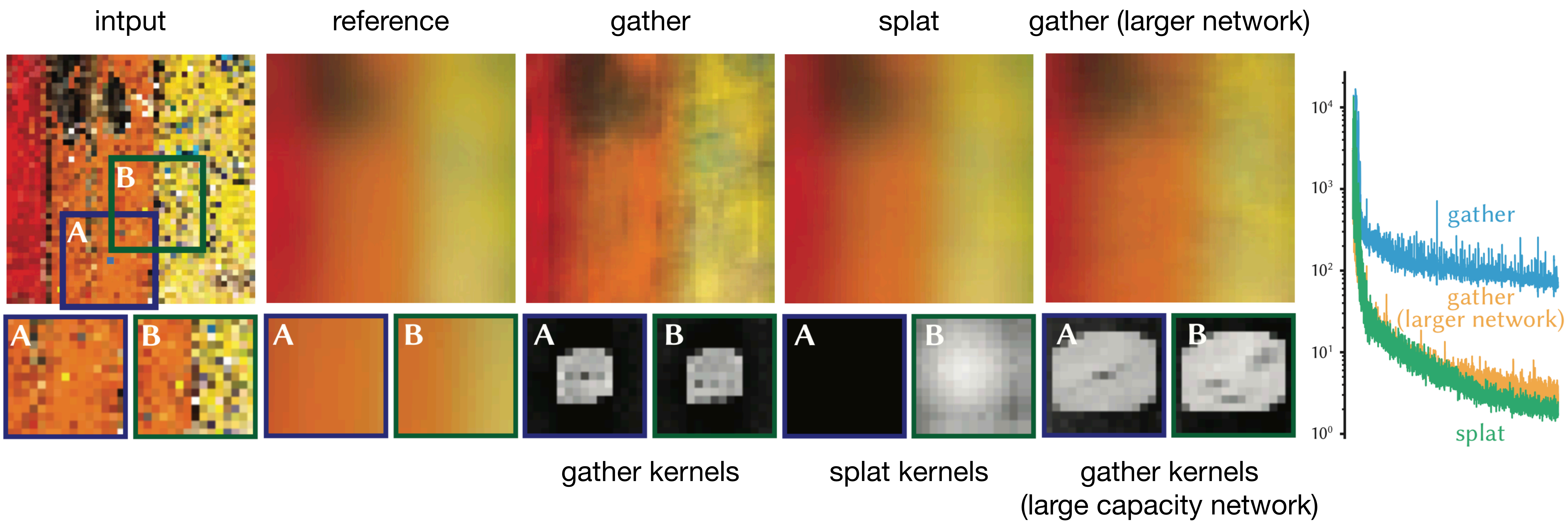
Kernel Splatting



Continue splatting kernels for the rest of the samples....

How do I contribute to nearby pixels, given all the samples around me?

Network: Kernel Gather vs Splatting



Permutation Invariance

Permutation Invariance

A model that produces the same output regardless of the order of elements in the input vector

Permutation Invariance: Example

 *  =

Permutation Invariance: Example

 *  = 

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Permutation Invariance: Example

Not Permutation Invariance


*

=

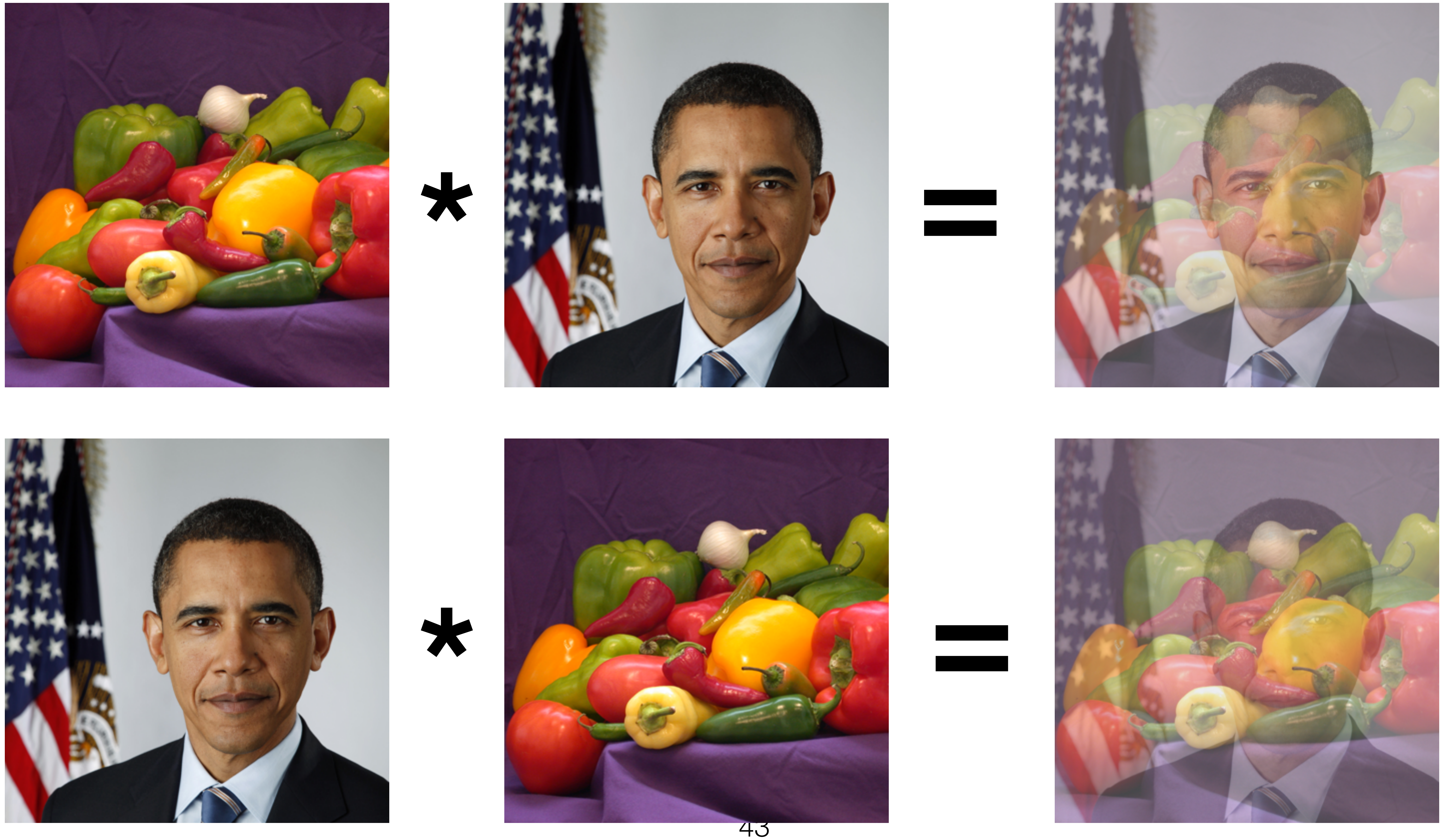


*

=

Permutation Invariance: Example

Not Permutation Invariance



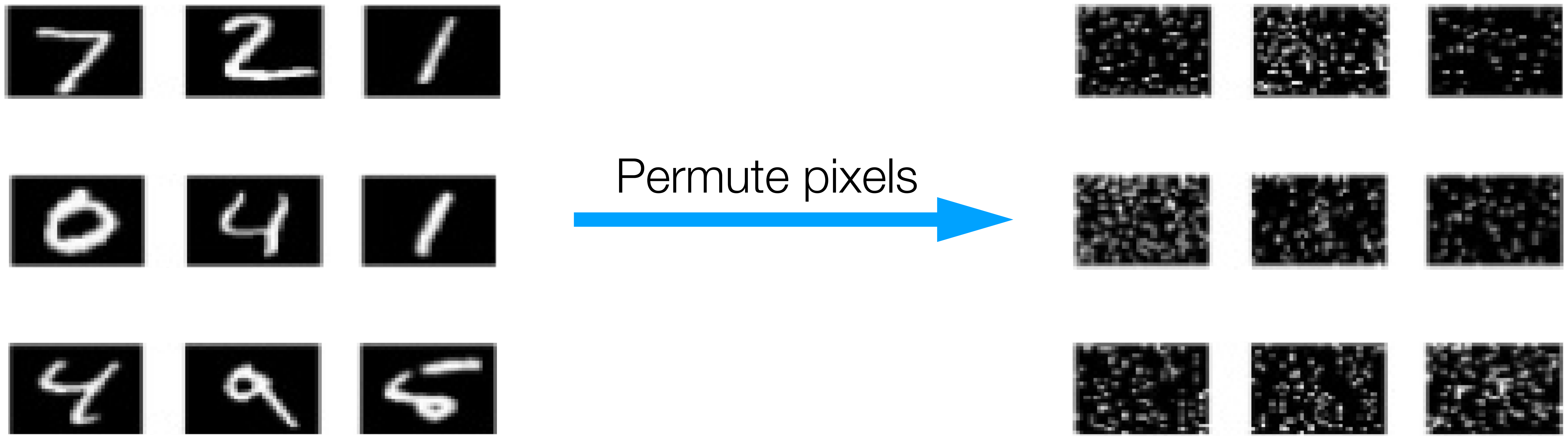
Permutation Invariance: Architectures

- A standard feedforward neural net such as multilayer perceptron (MLP) is insensitive to order of elements in input vector - so it is inherently permutation insensitive

- However, both a Convnet and RNNs for instance make full use of input ordering - they are permutation sensitive.

Permutation Invariance: Example

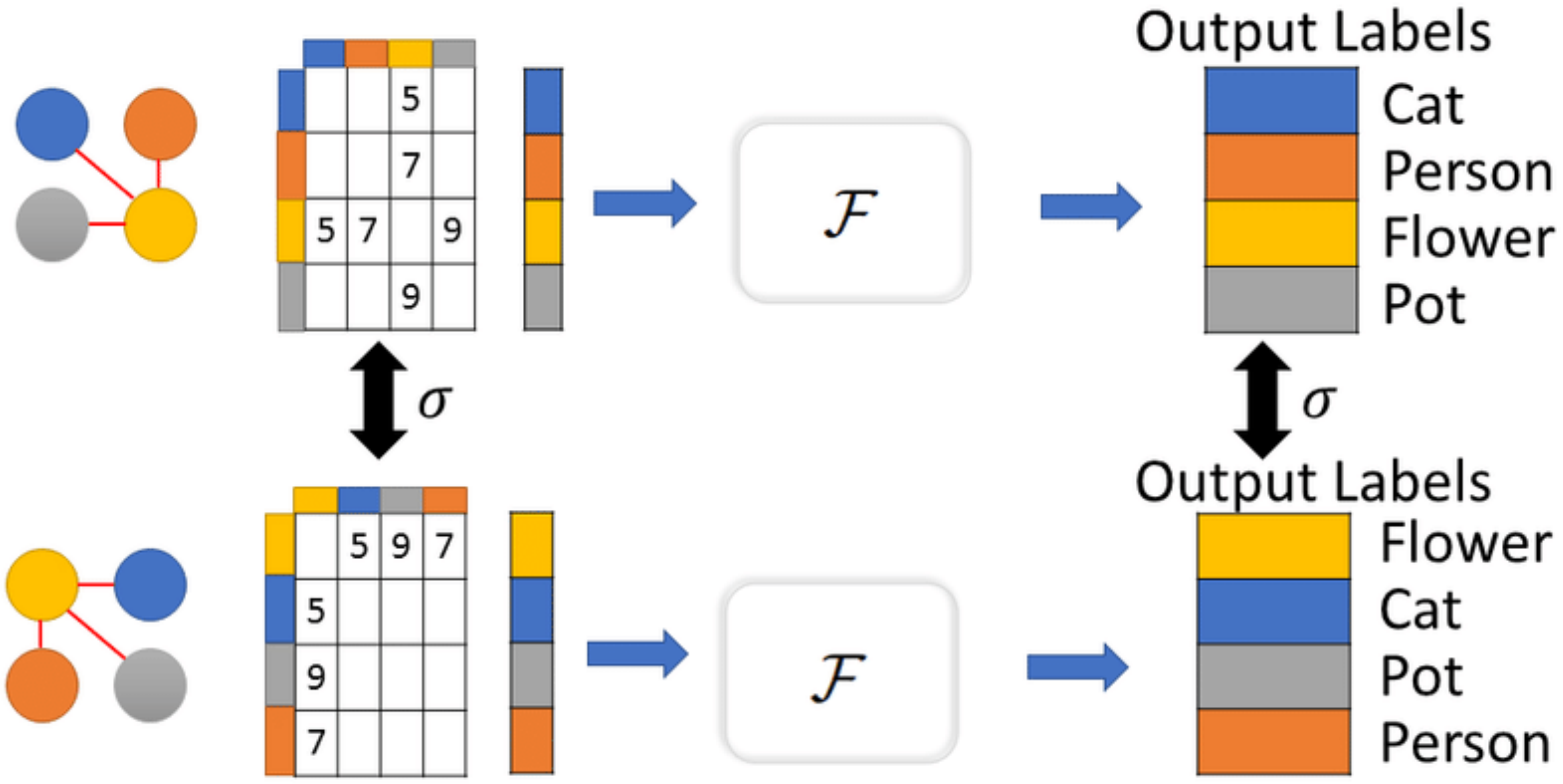
MNIST Dataset



Permuting pixels makes it difficult for humans to understand the images.

However, permutation invariant networks like MLP can detect digits irrespective of the order of pixels

Permutation Invariance: Example

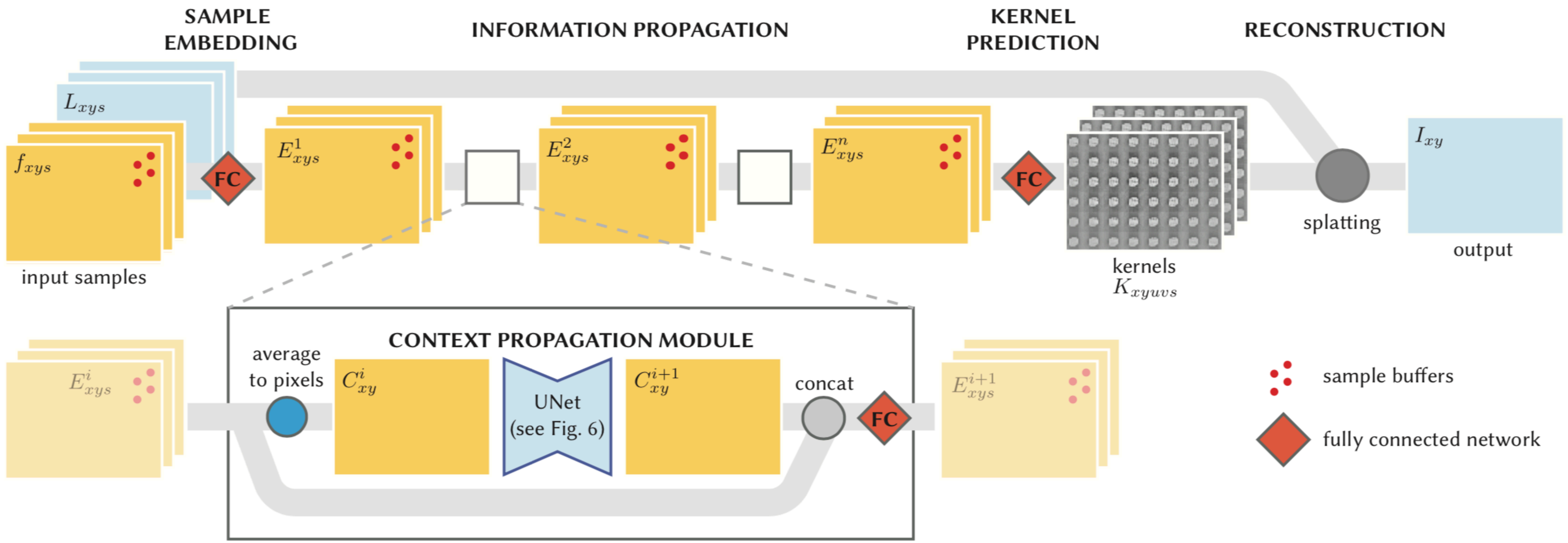


A graph labeling function F is graph permutation invariant (GPI) if permuting the names of nodes maintains the output. Herzig et al.[2018]

Permutation Invariance

- In MLPs, since each component is connected to each other, the order does not matter
- In structured convolutions, the order matters and therefore, it is not permutation invariant.

Proposed Network Architecture



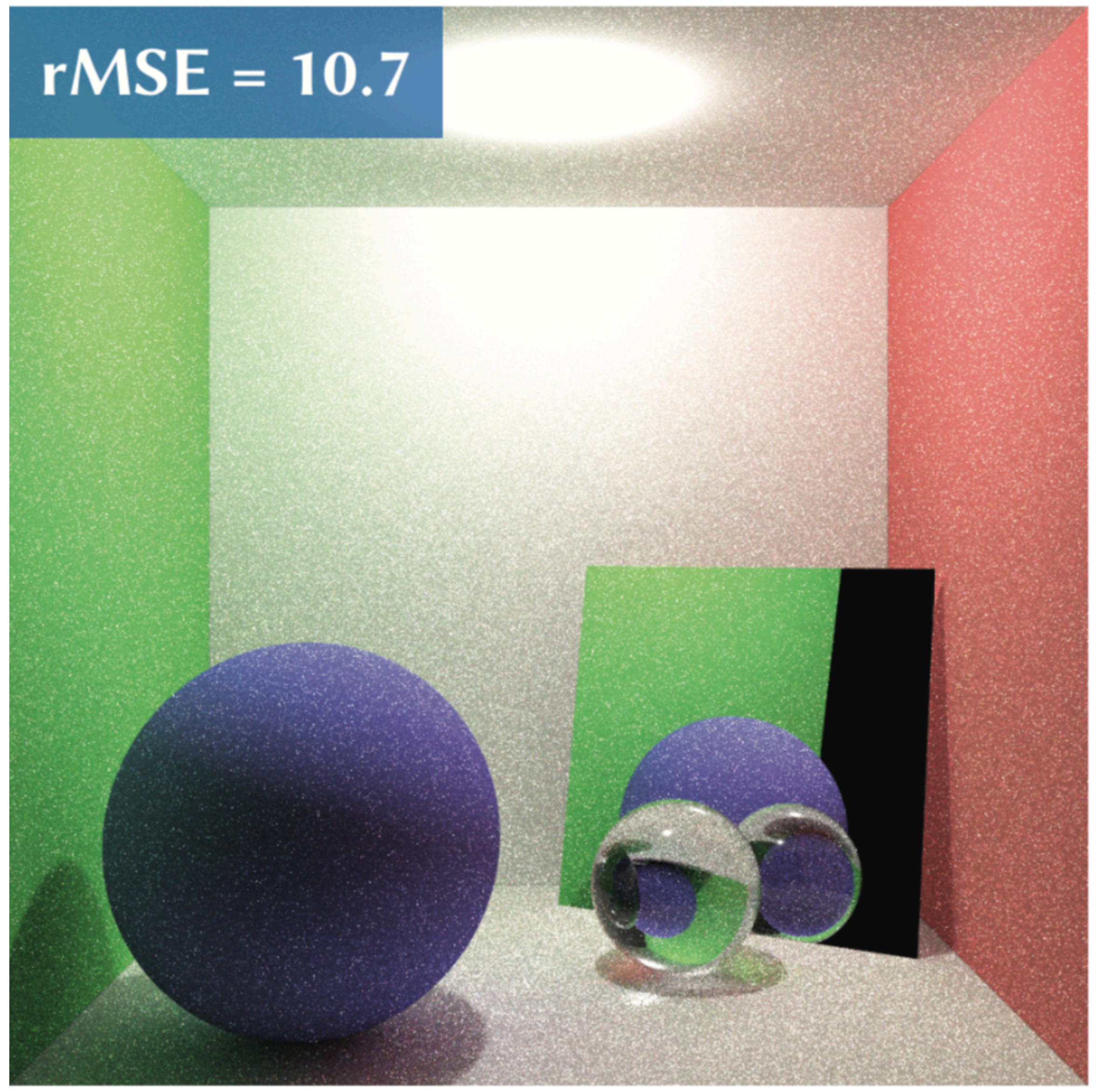
Dataset and Training Procedure

Procedurely generated dataset: 300,000 renderings with 128x128 resolution

Also generated input buffer (4, 32 spp), but this time also maintained auxiliary features

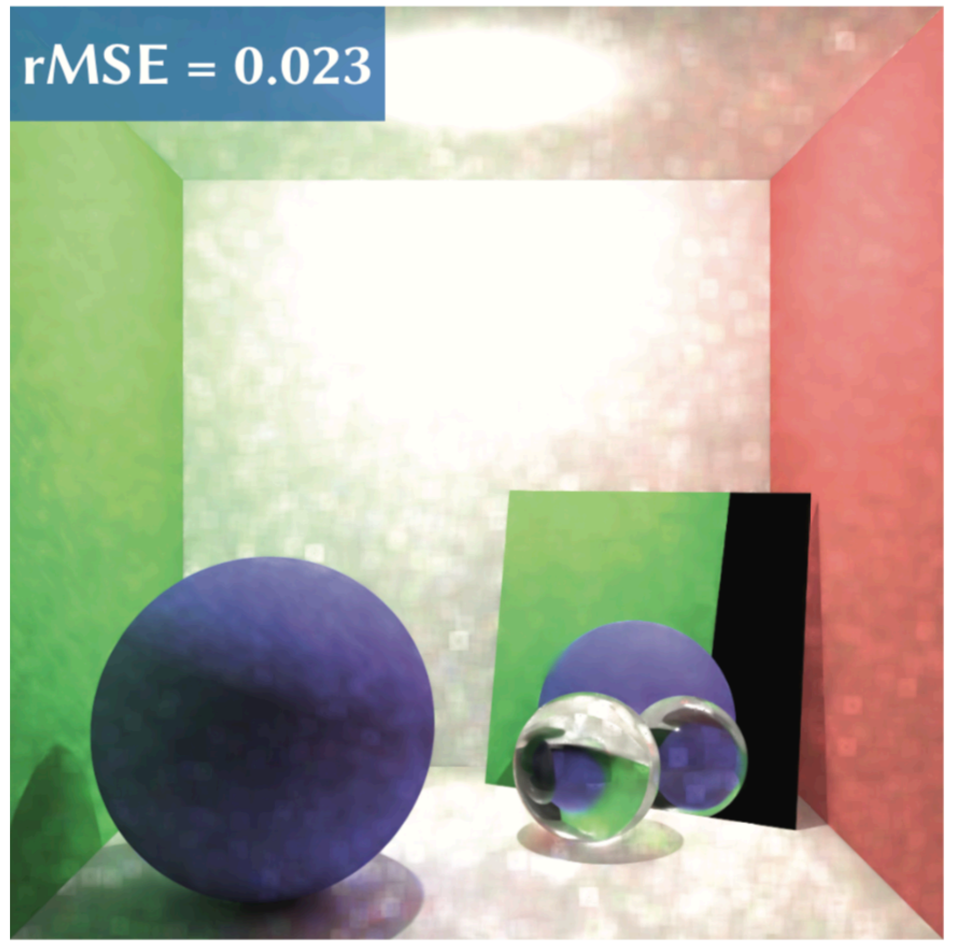
Reference was generated for 4096 samples

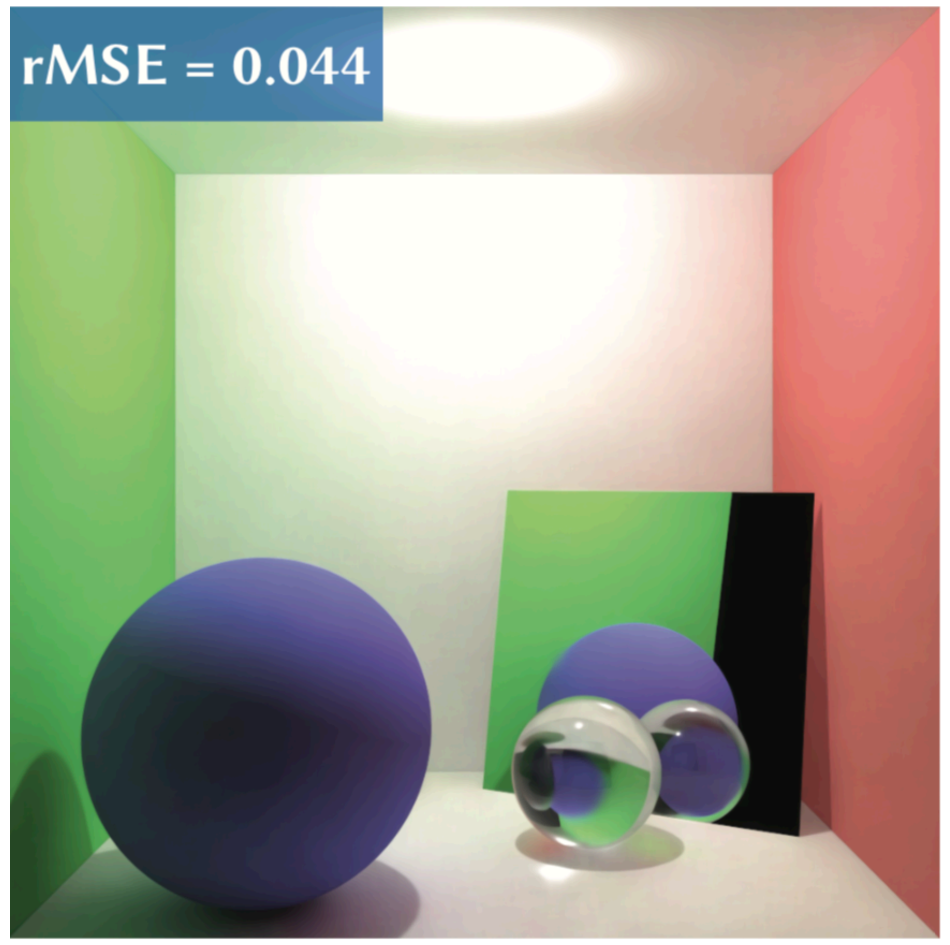
Splat vs Gather



Input

per sample gather

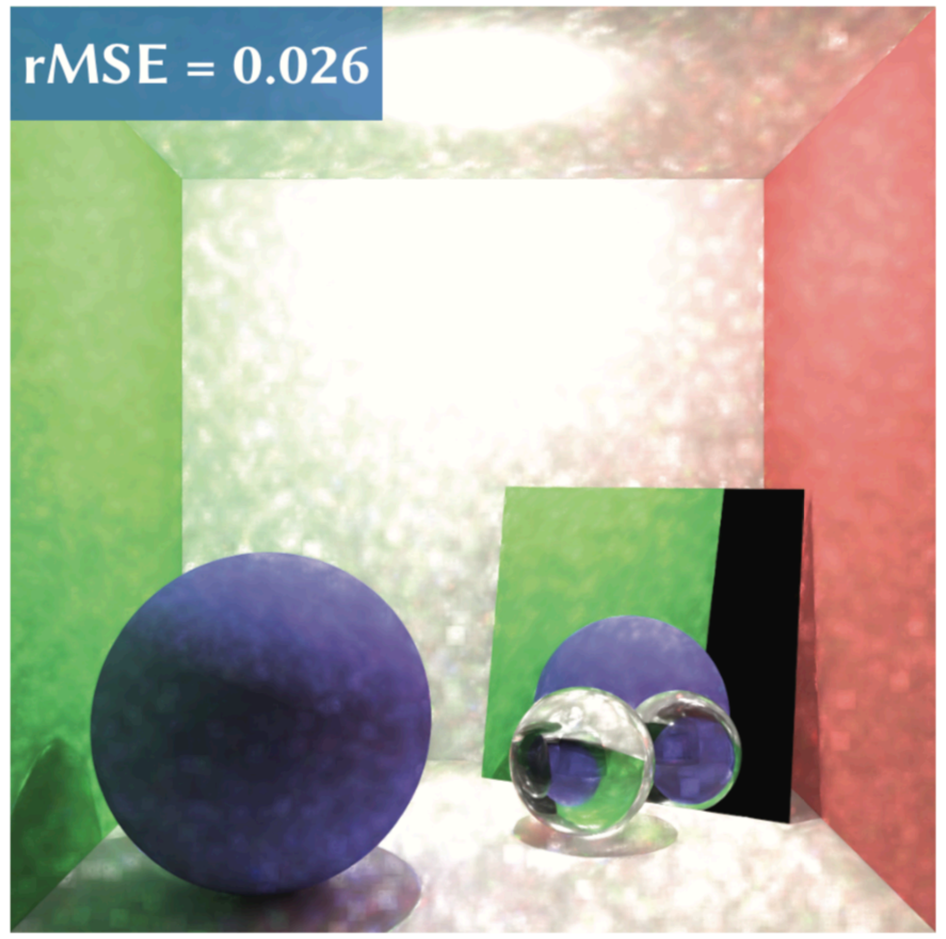


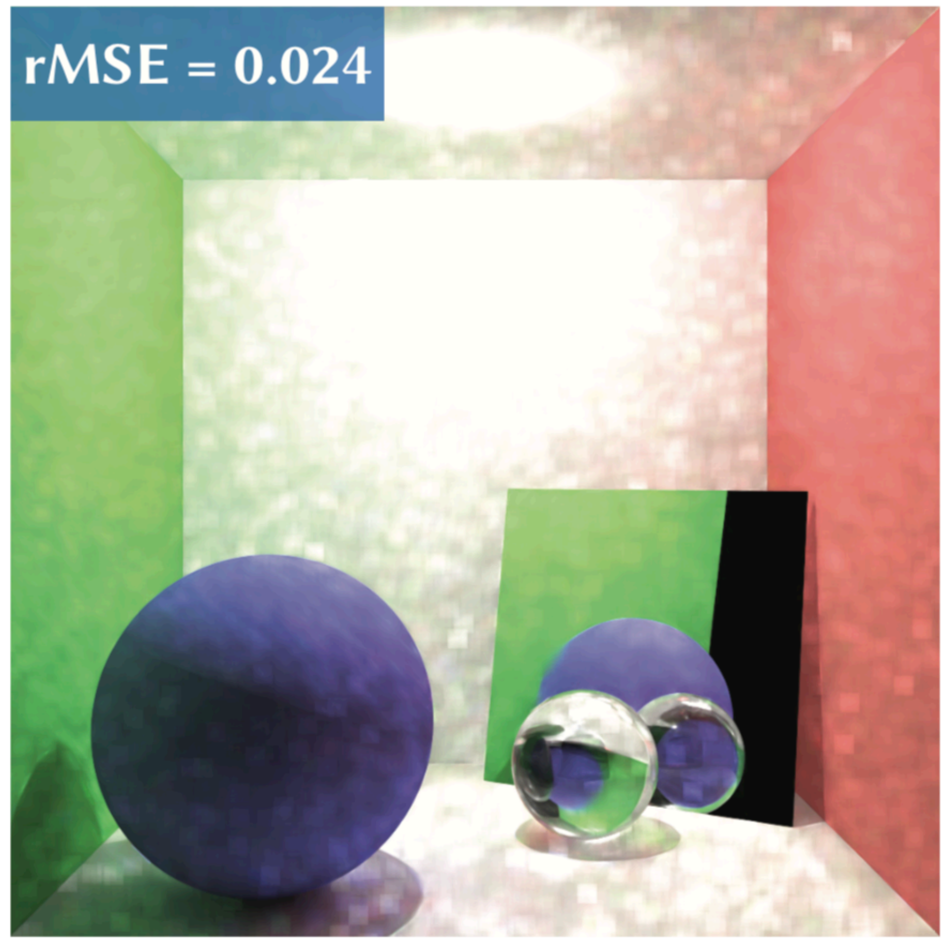


per sample splat

Reference

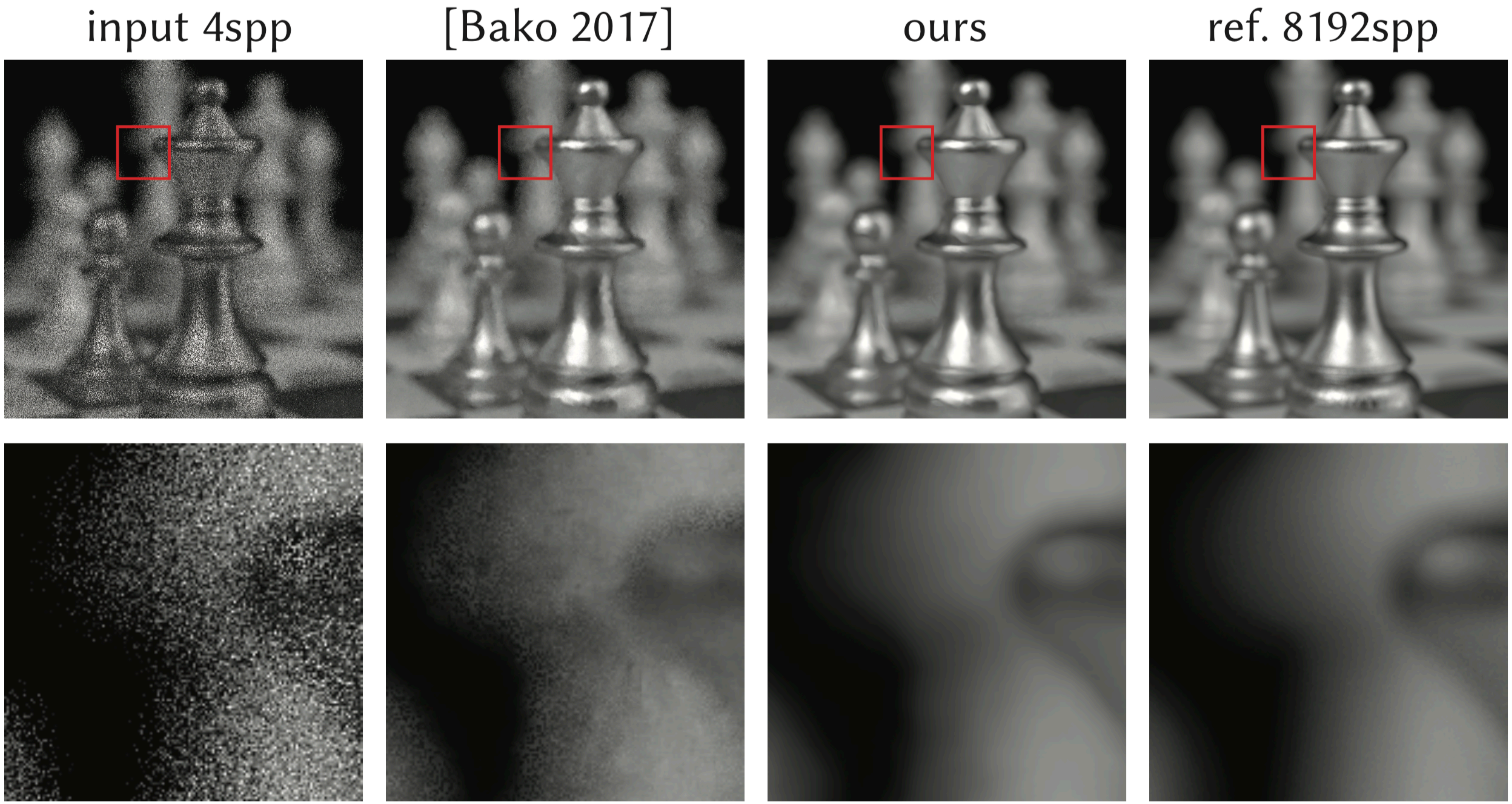
per pixel gather





per pixel splat

Results



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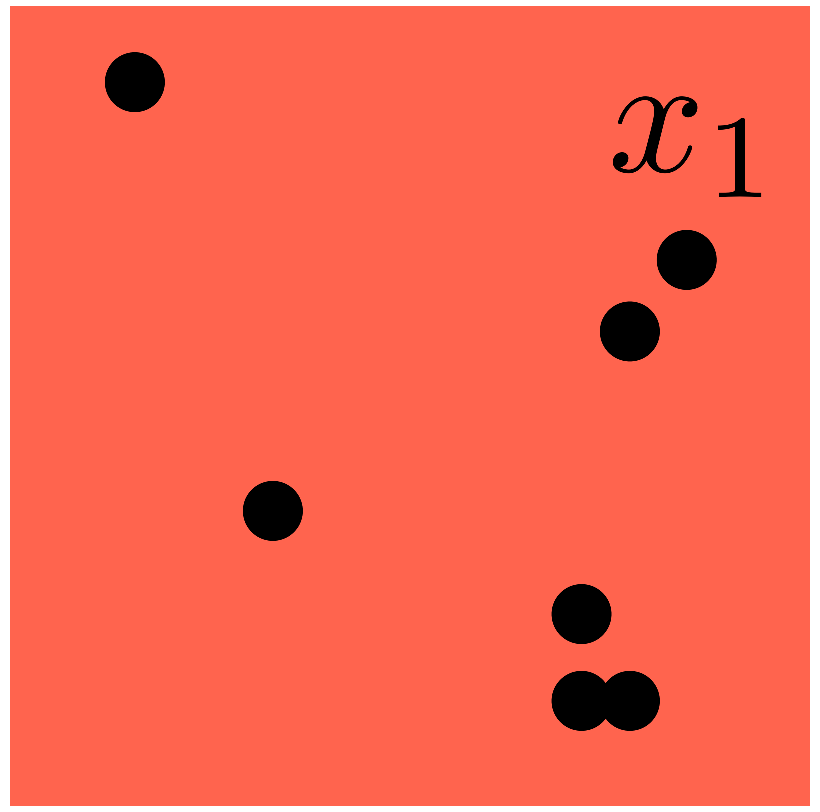
Network Architecture Comparisons

(Deep) Convolutional Neural Networks

Based on Convolutional Neural Networks

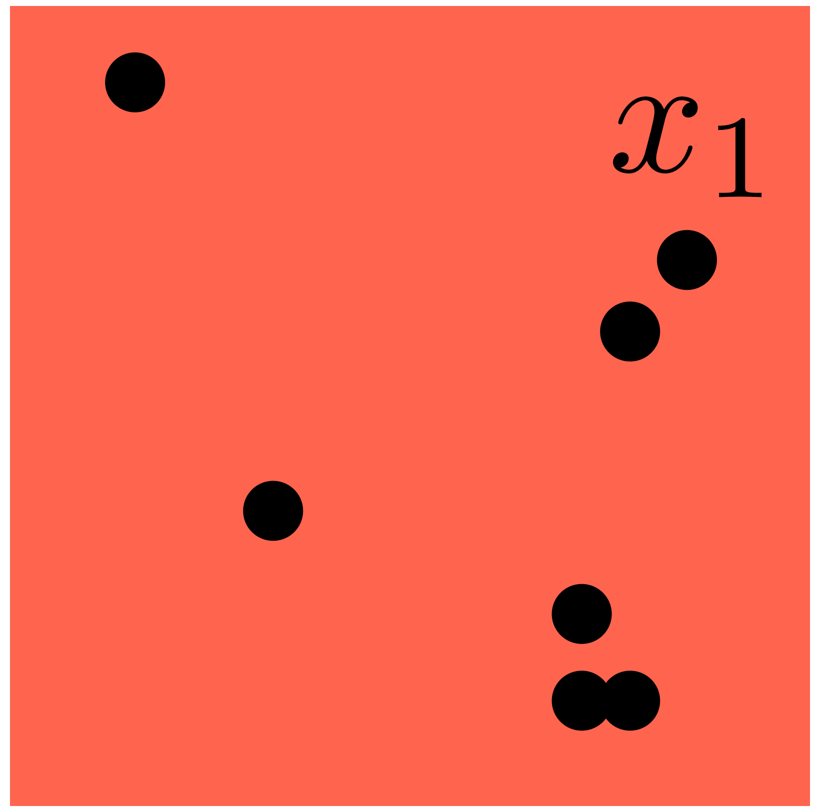
Unstructured data



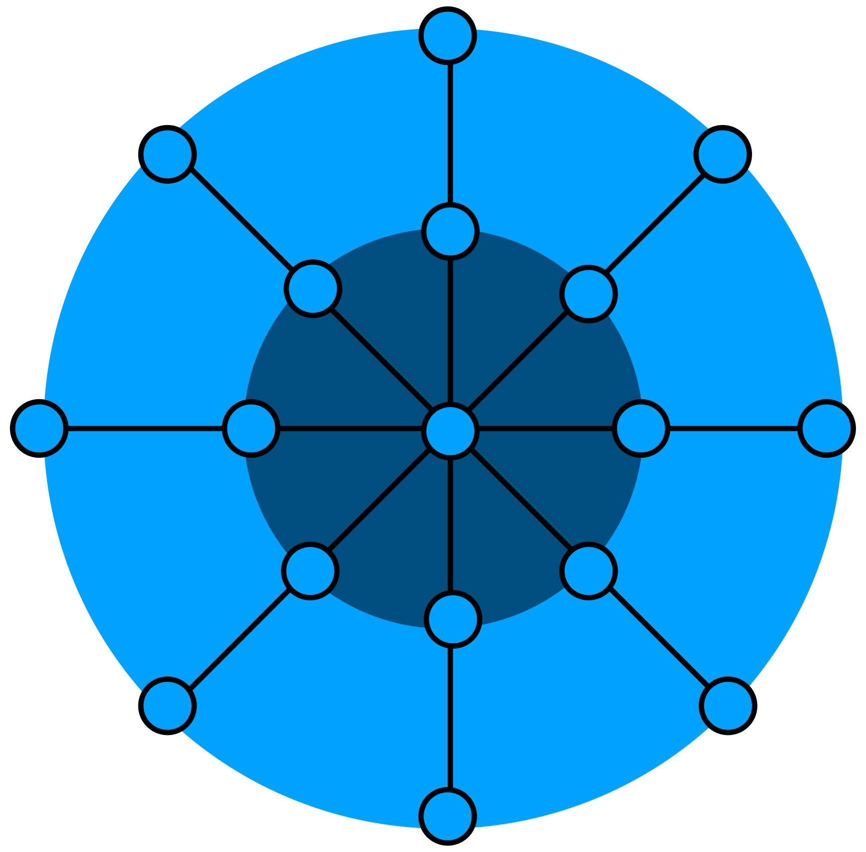
N number of point samples

Based on Convolutional Neural Networks

Unstructured data



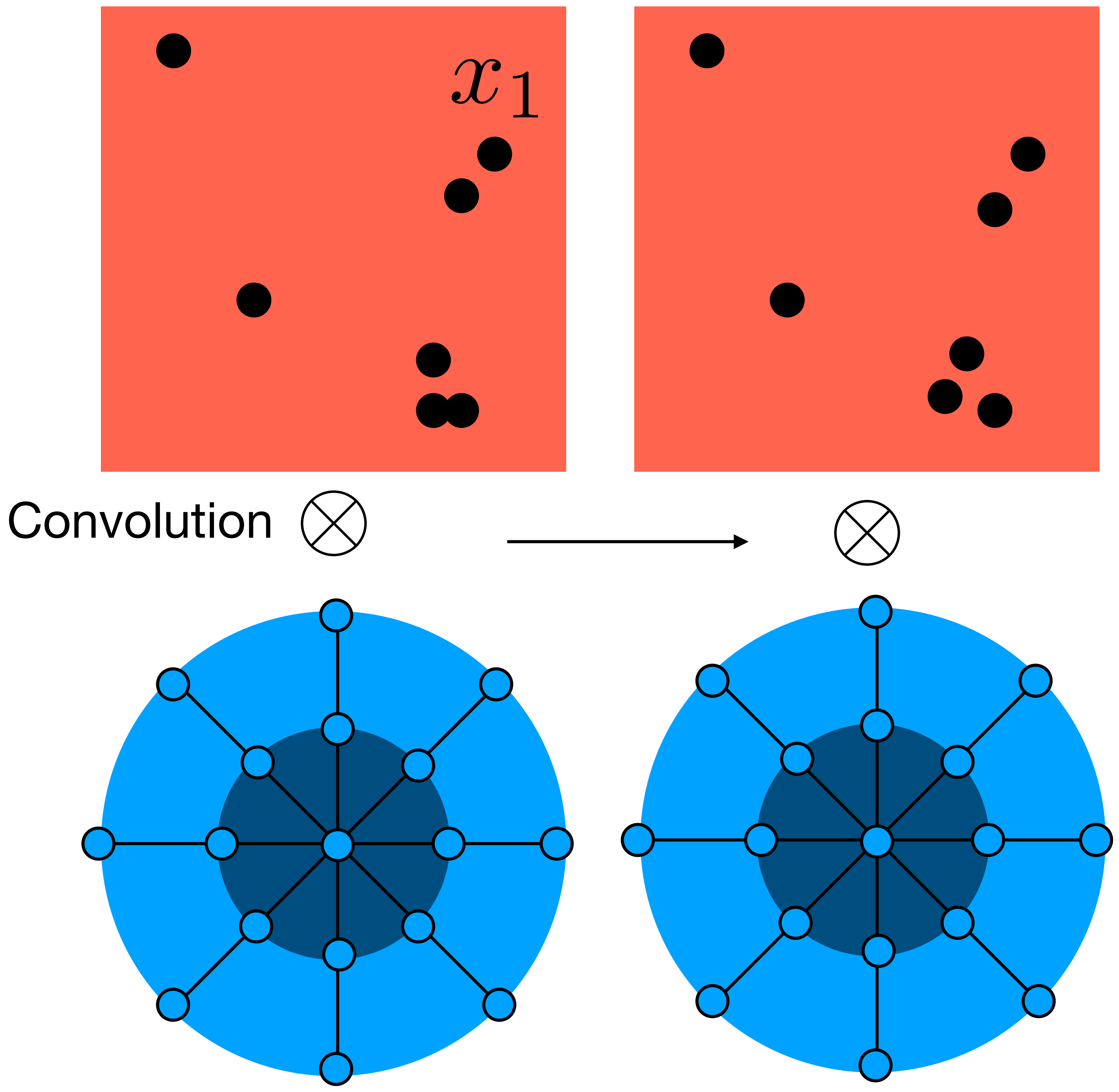
Convolution $\otimes$



N number of point samples

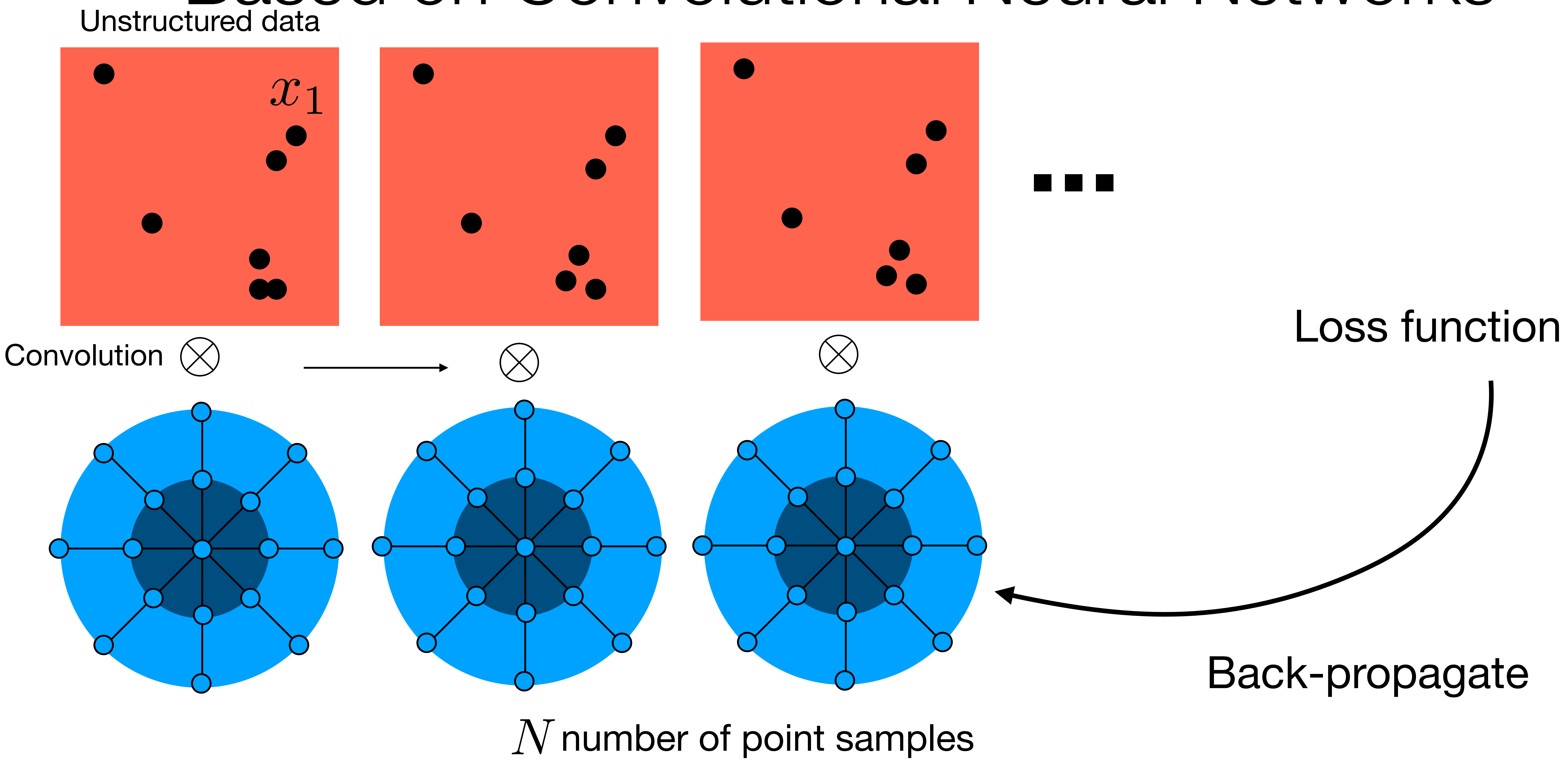
Based on Convolutional Neural Networks

Unstructured data



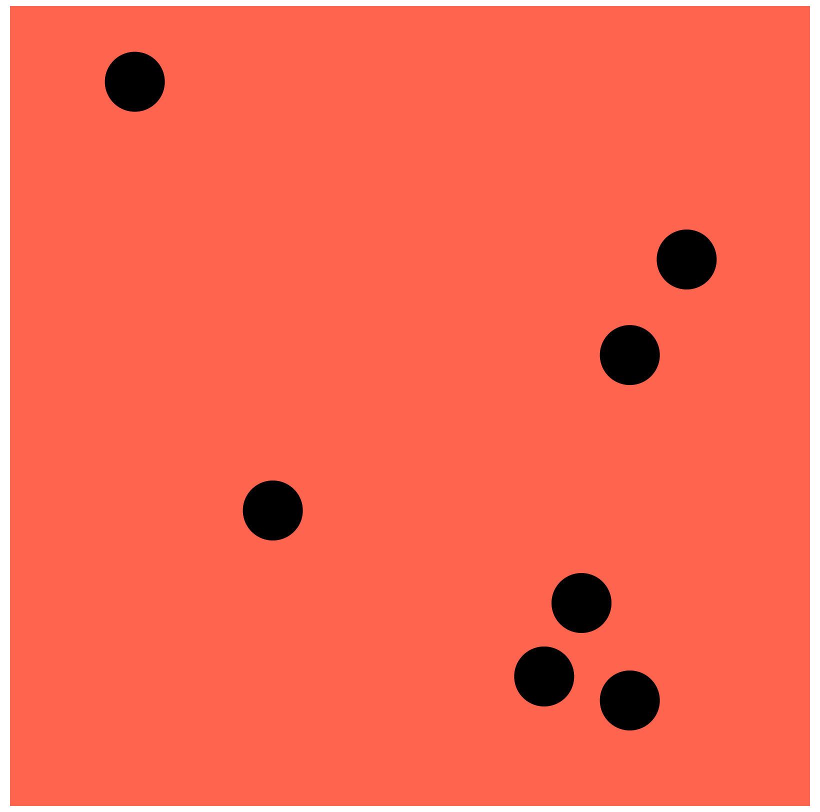
N number of point samples

Based on Convolutional Neural Networks

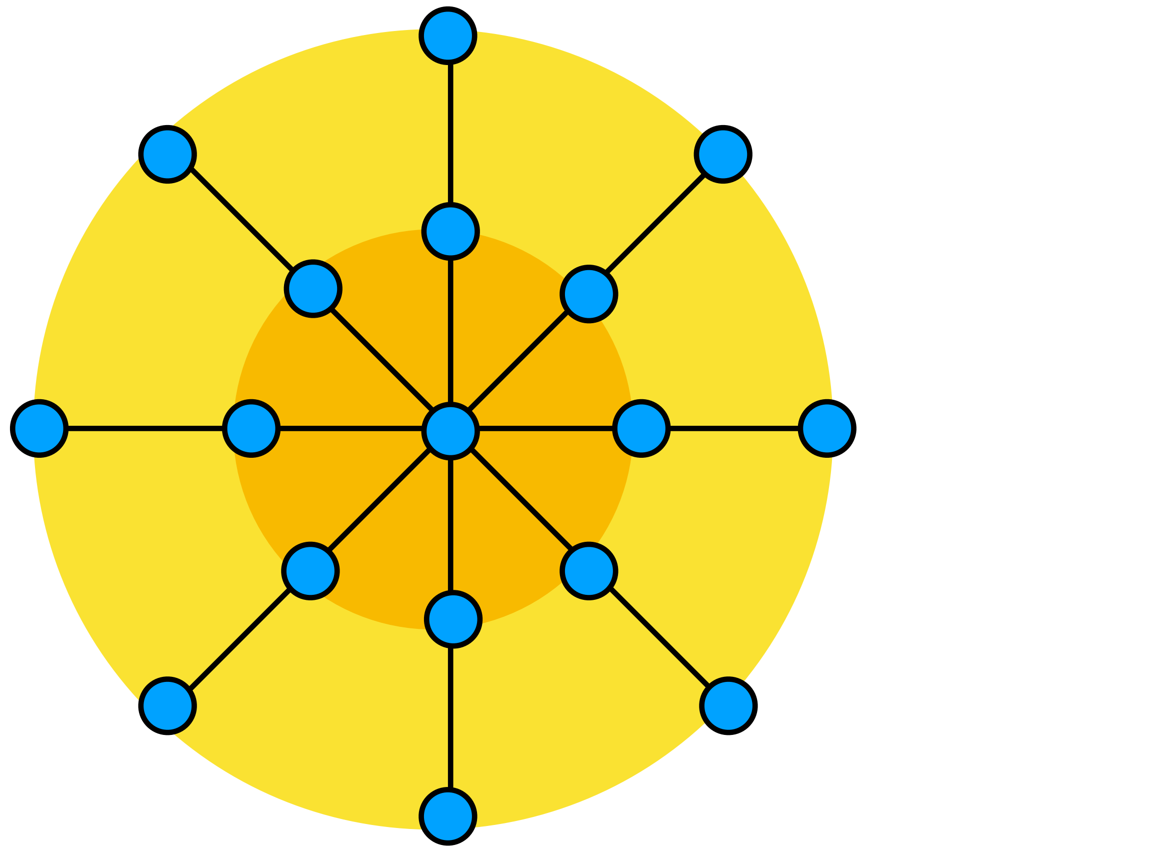


Based on Convolutional Neural Networks

Unstructured data

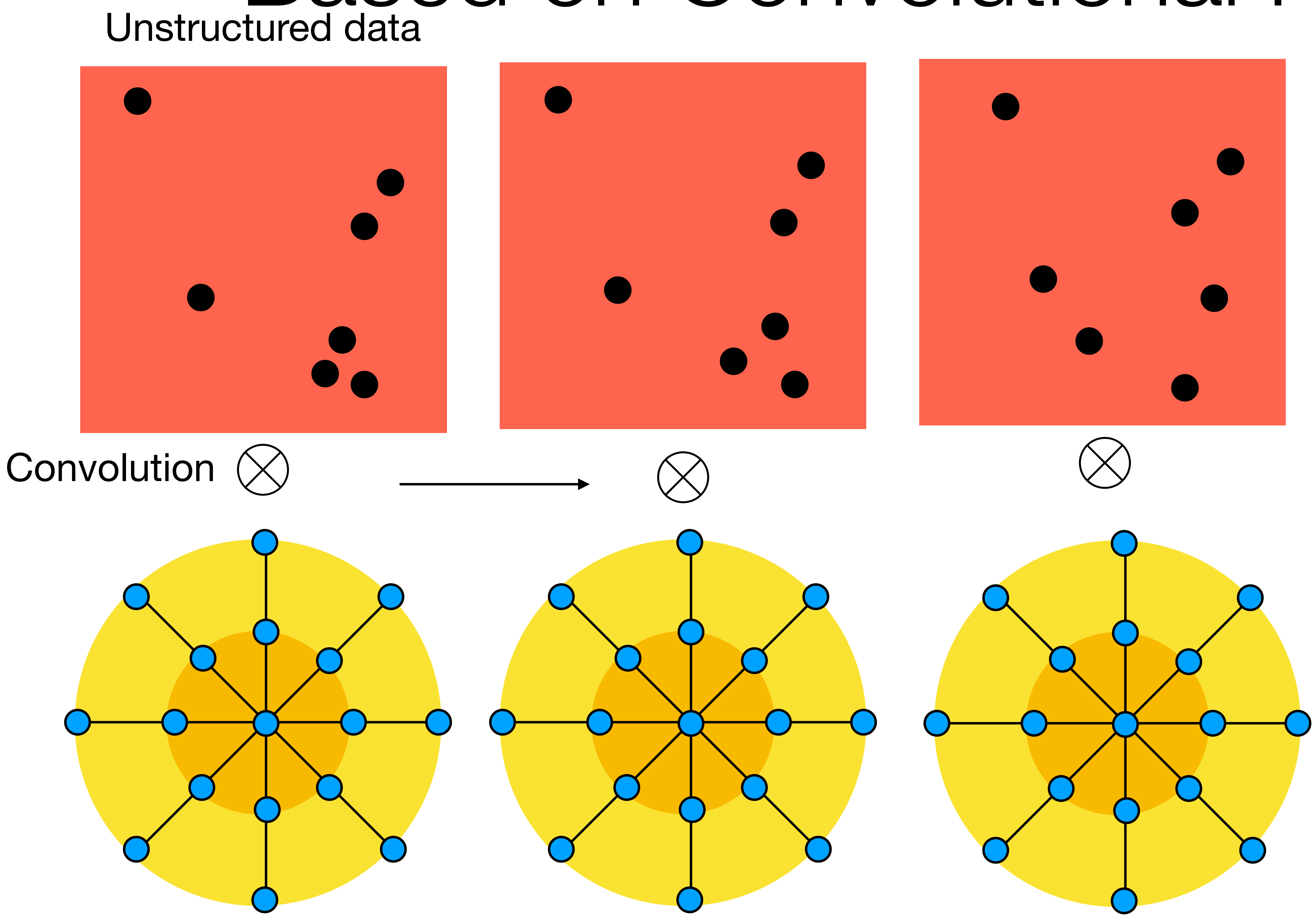


Convolution ⊗



N number of point samples

Based on Convolutional Neural Networks

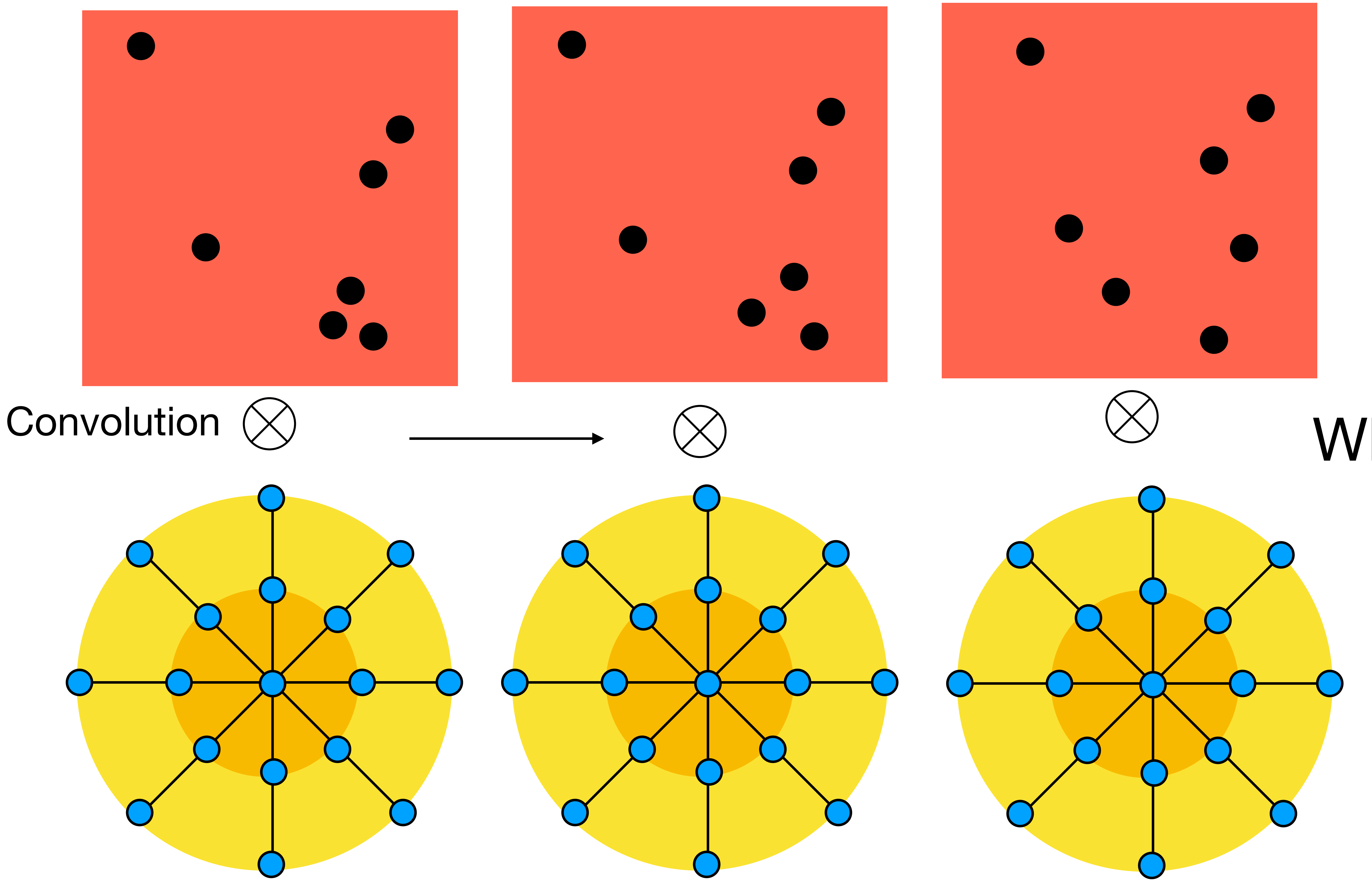


Keep training the network!

N number of point samples

Based on Convolutional Neural Networks

Unstructured data



■ ■ ■ Keep training the network!

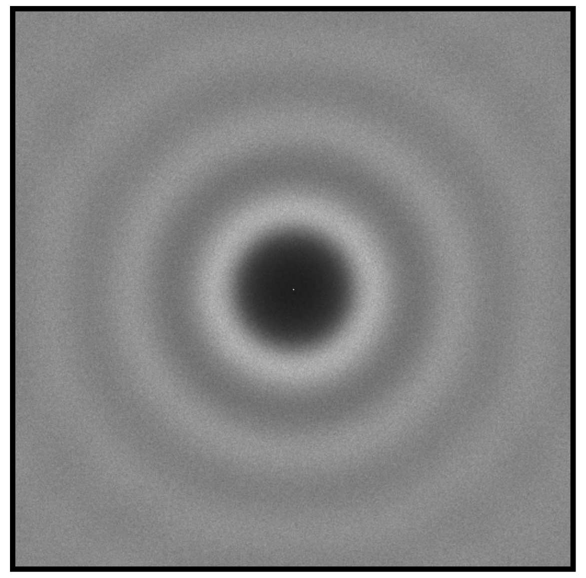
Which Loss function can we use?

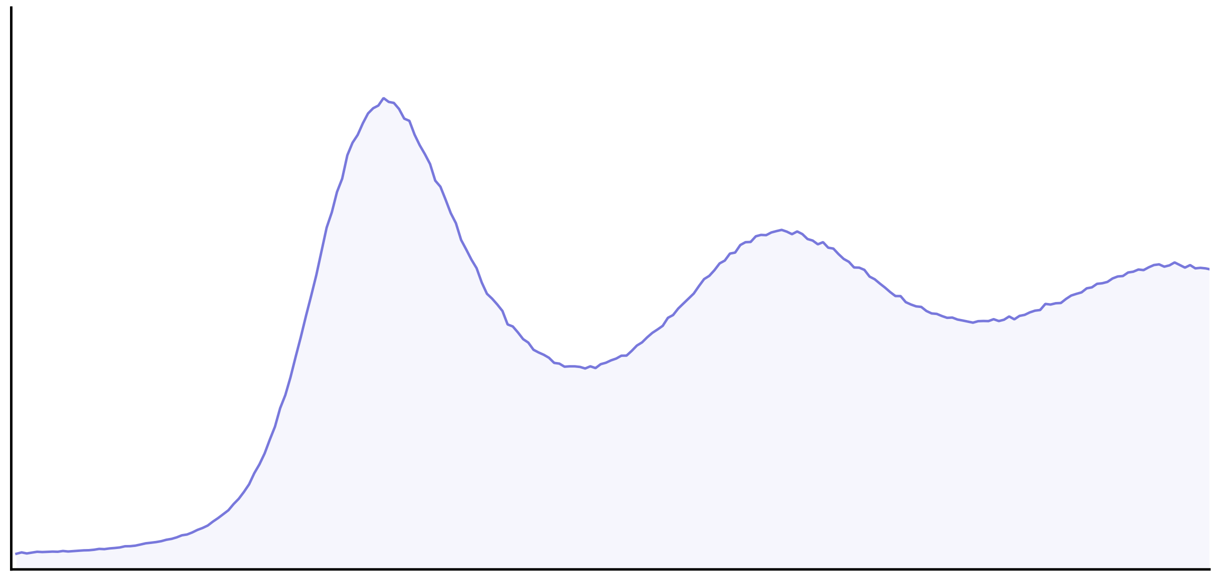
N number of point samples

Spectral Loss Function

Spectral Loss at i-th training iteration

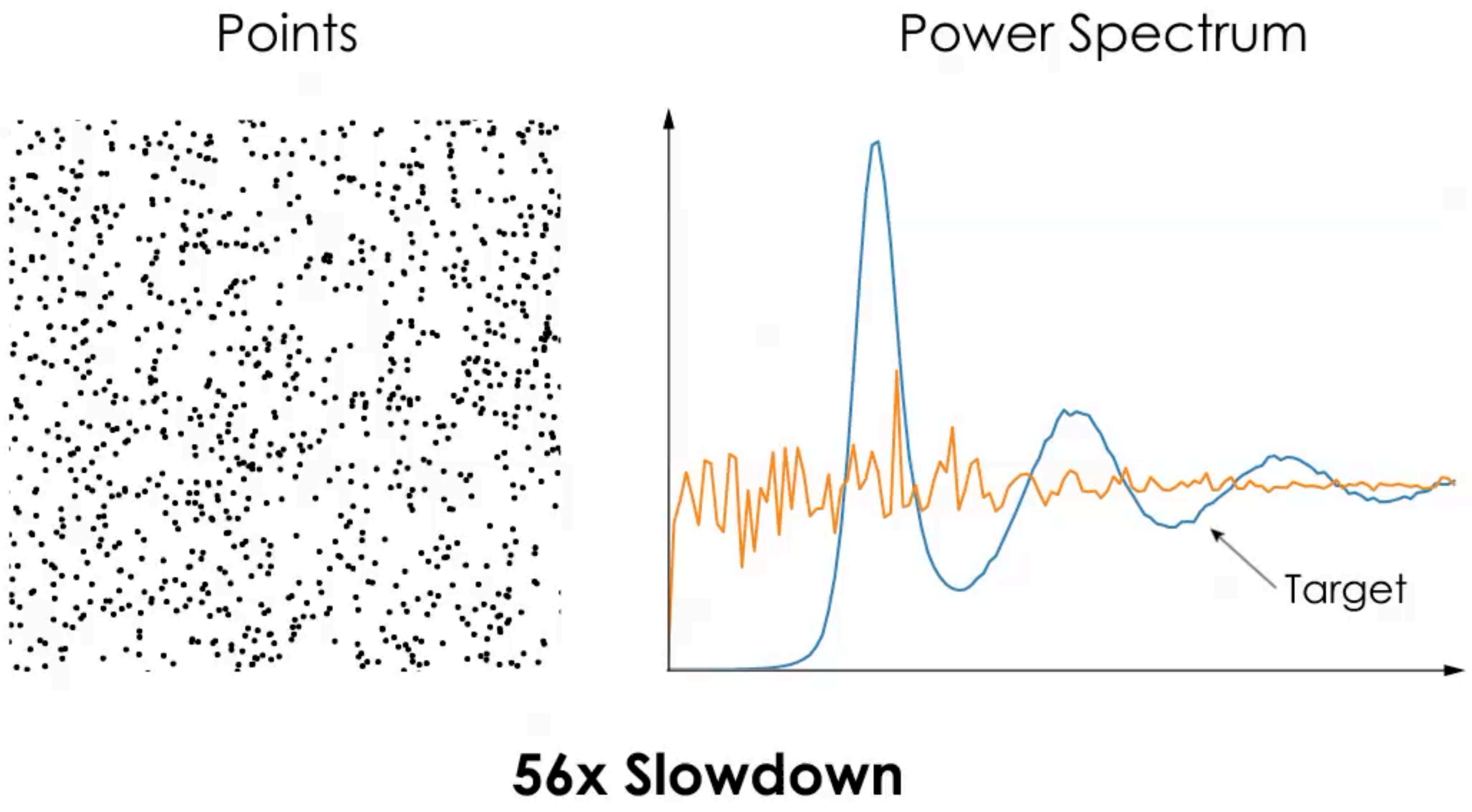
$$L_{\text{spectral}} = ||\langle \mathcal{P}_i(\nu) \rangle - \langle \mathcal{P}(\nu) \rangle||^2$$

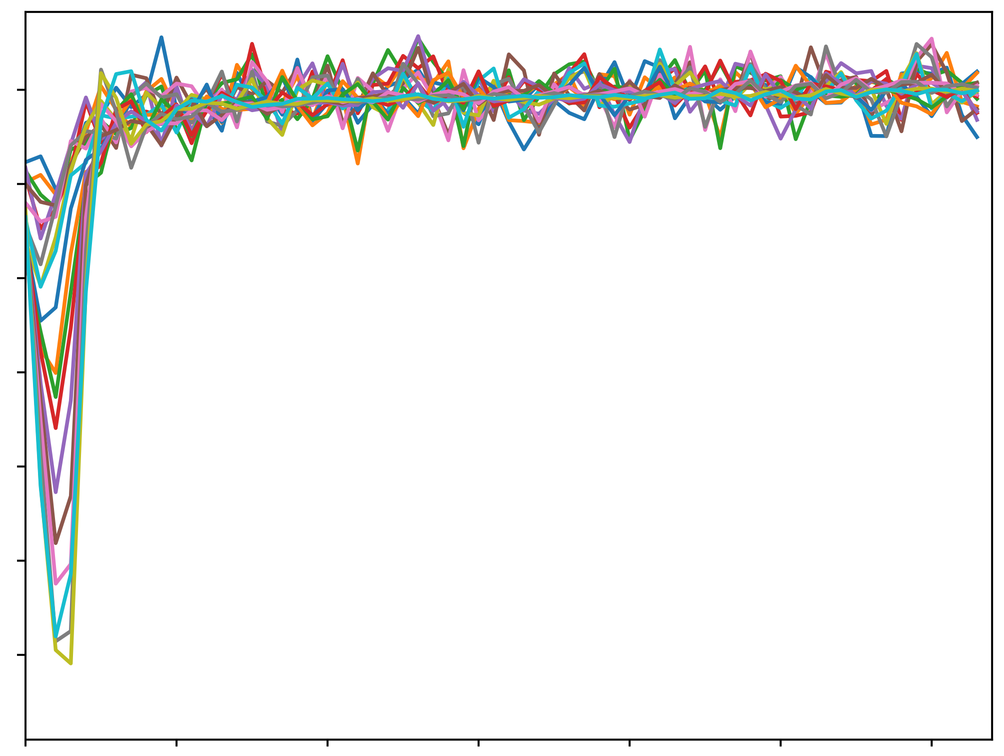




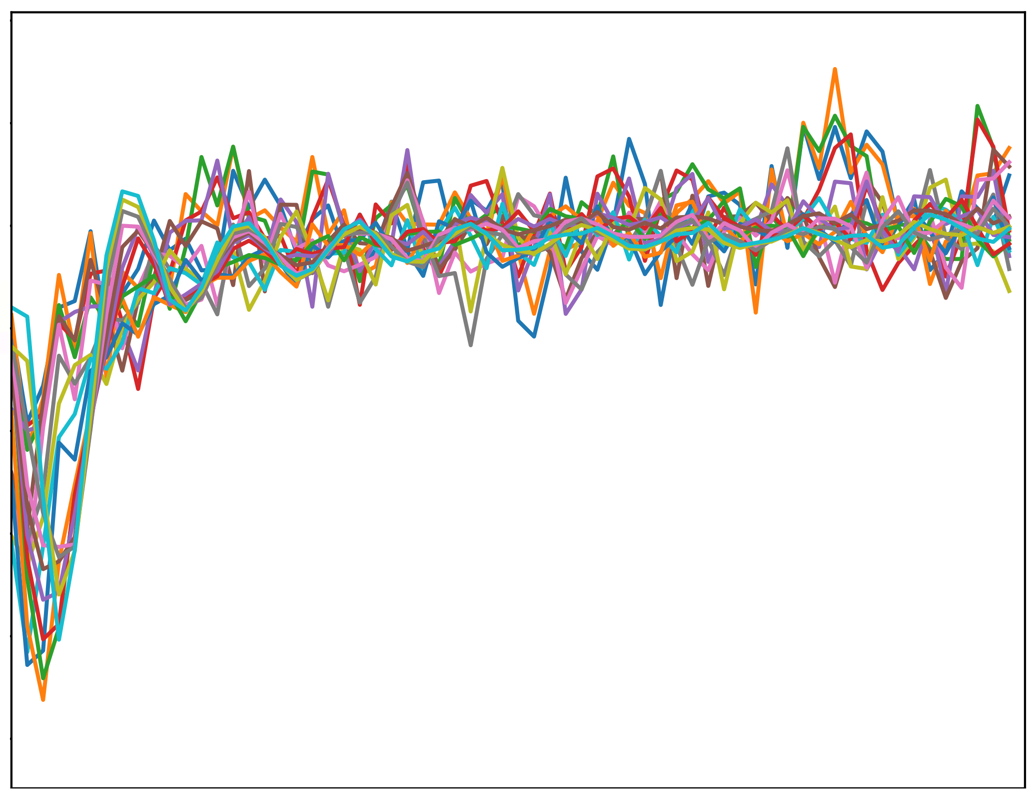
Radially averaged power

Training Process



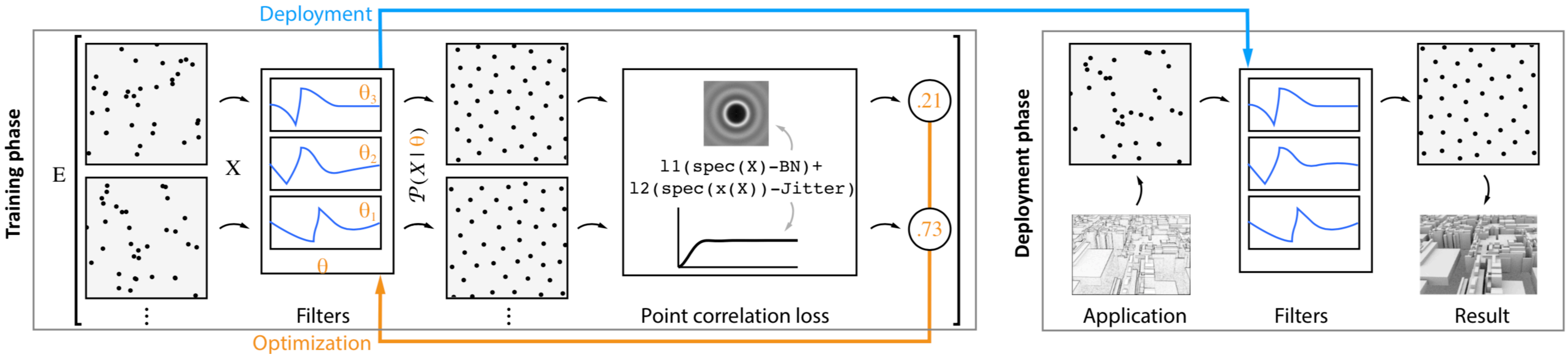


Kernels for BNOT
(de Goes et al.[2012])

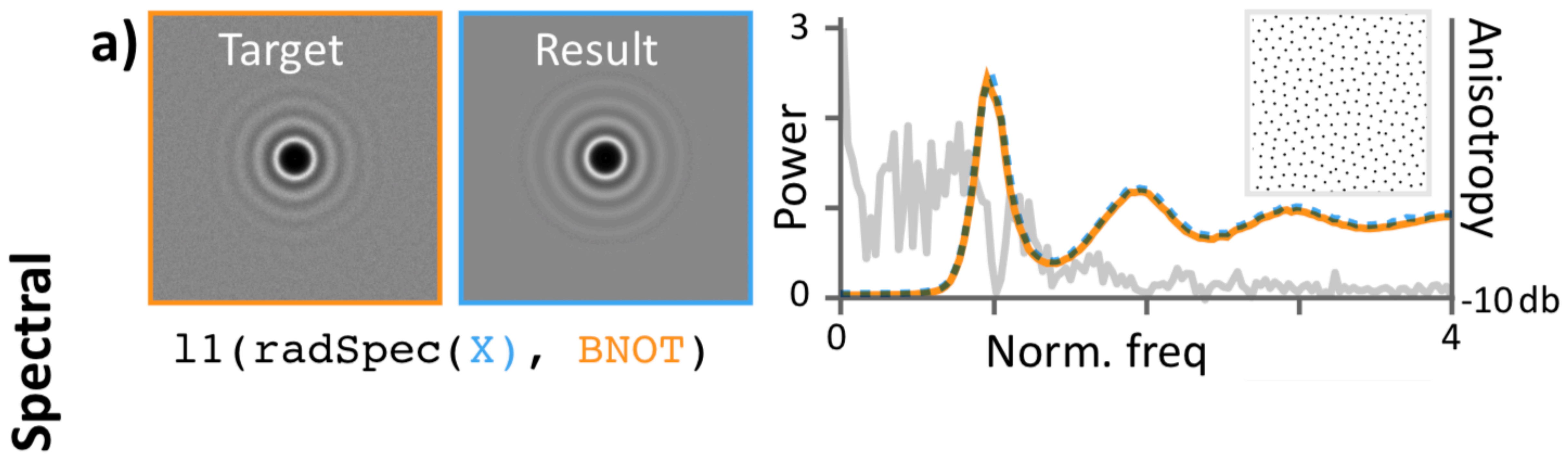


Kernels for Step
(de Heck et al.[2013])

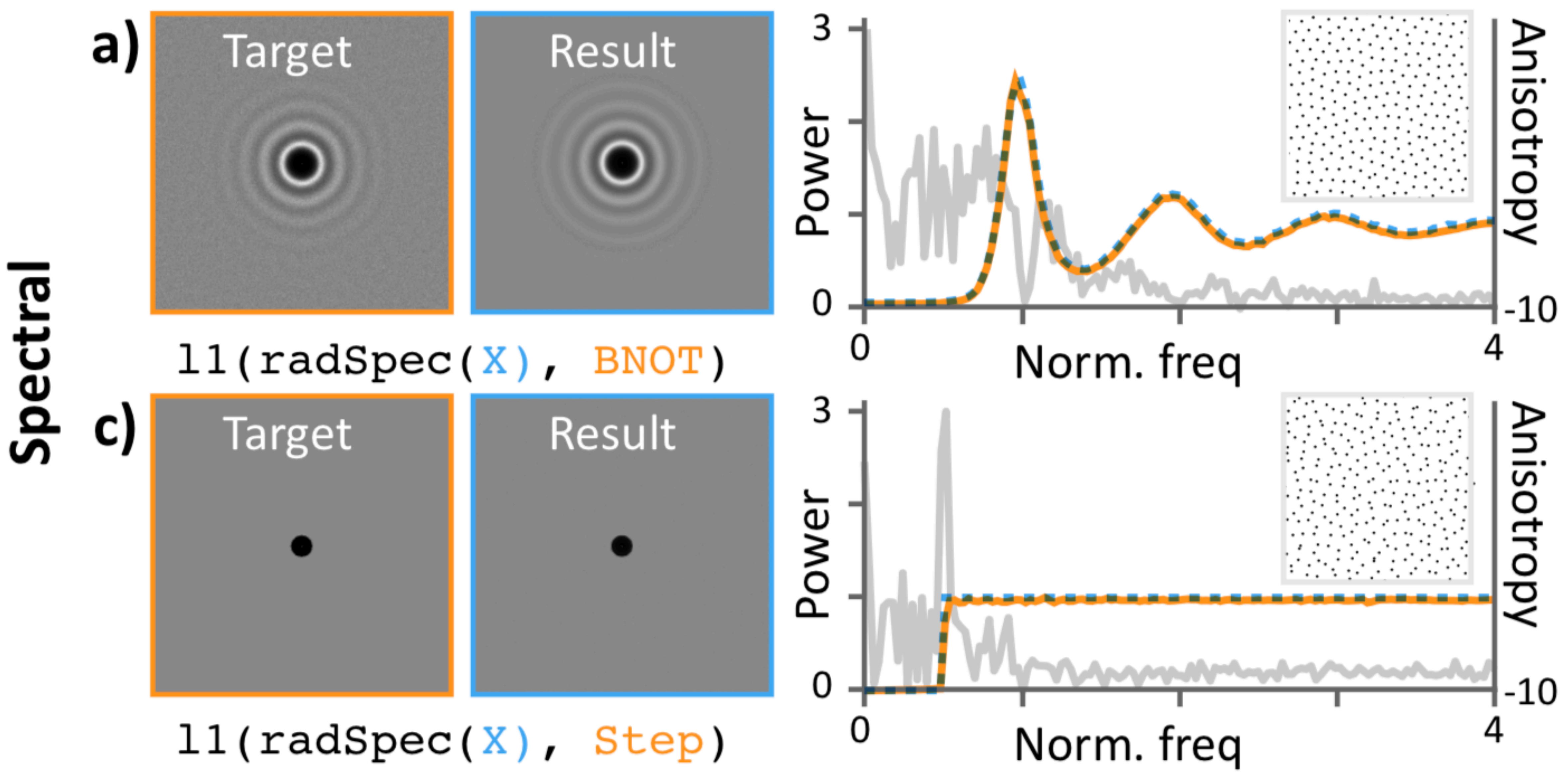
Architecture: Full pipeline



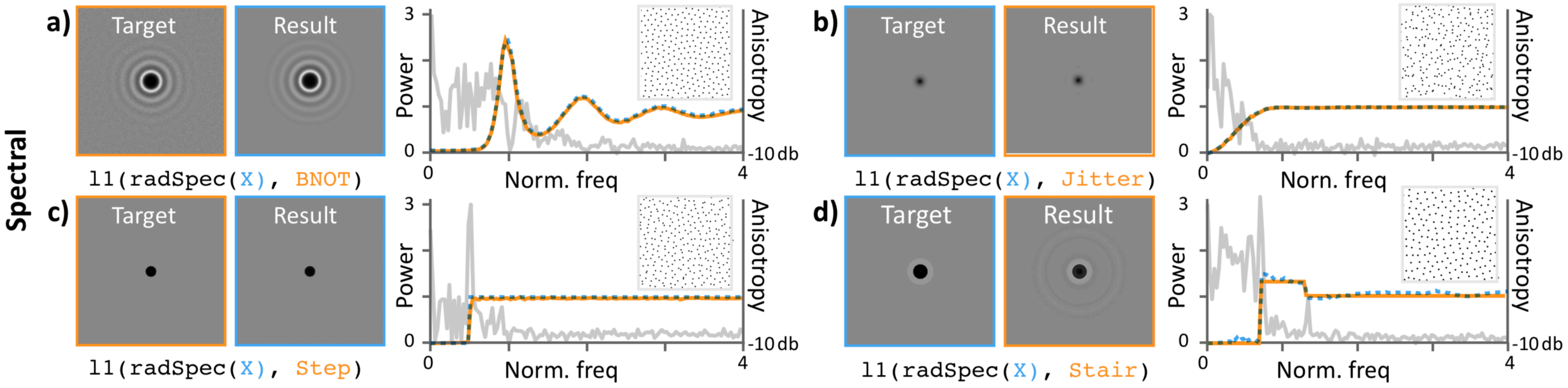
Results: Spectral Target Spectra



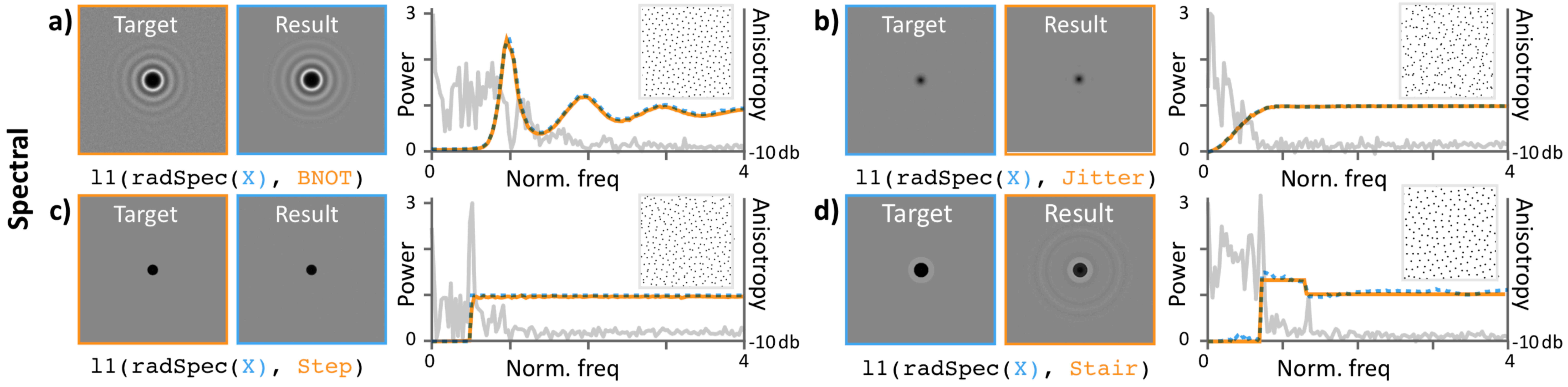
Results: Spectral Target Spectra

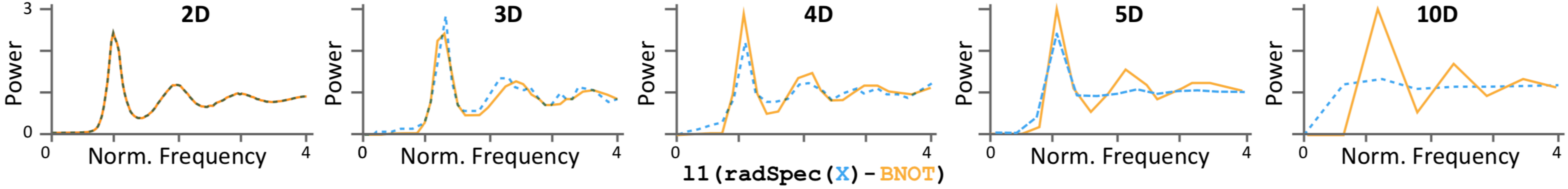


Results: Spectral Target Spectra



Results: Spectral Target Spectra

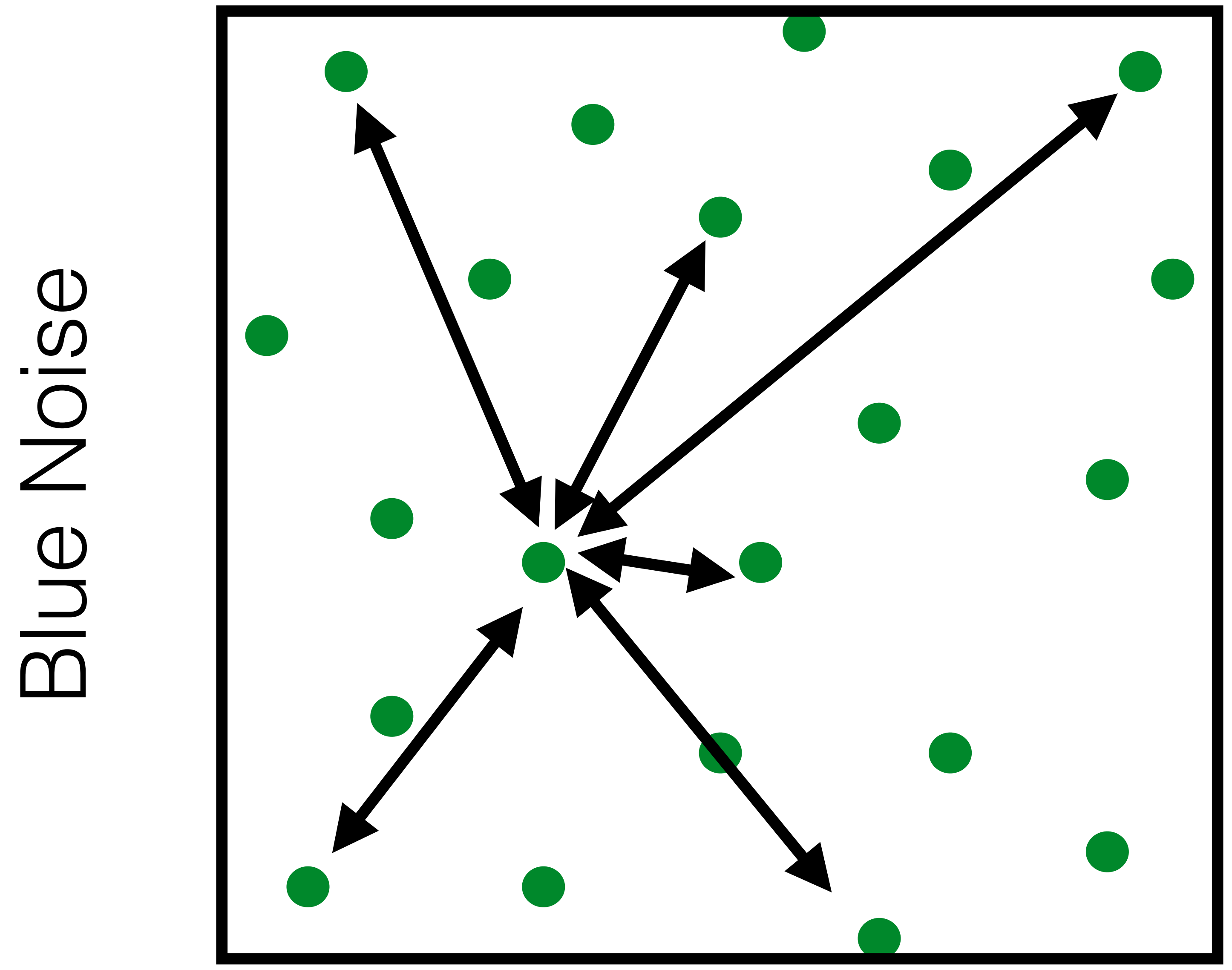


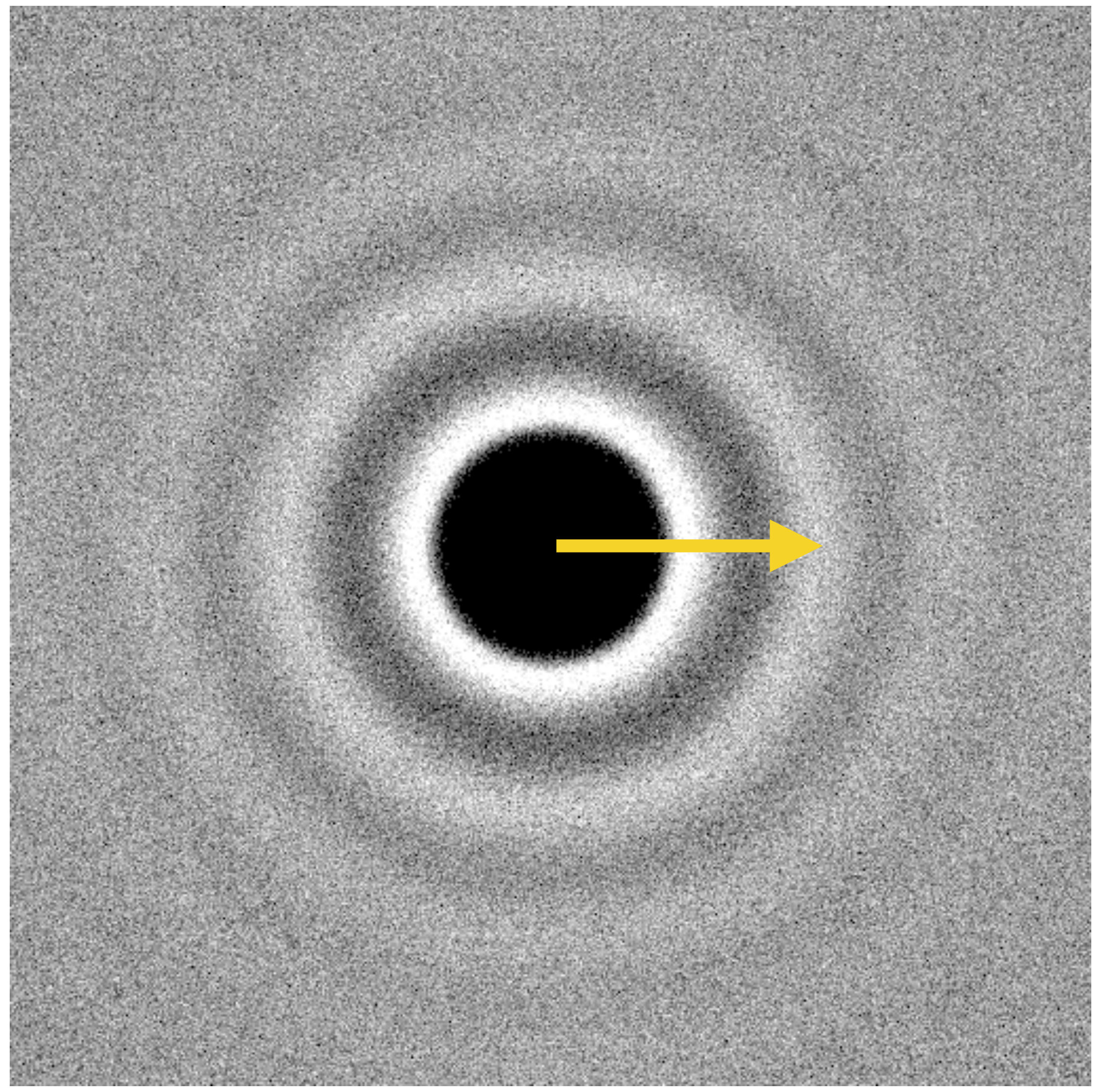


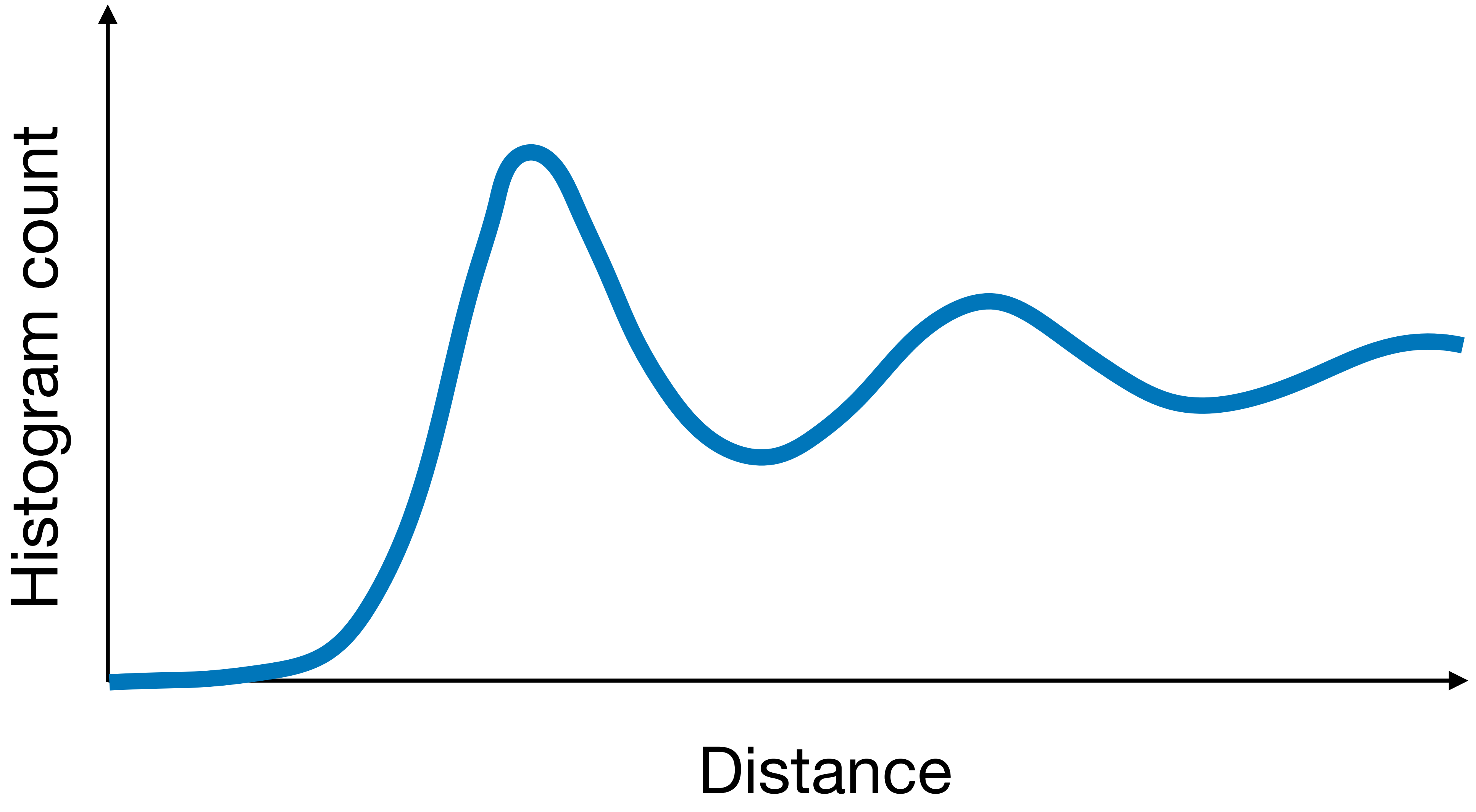
Spatial Loss Function

PCF Loss at $i\text{-th}$ training iteration

Spatial Domain



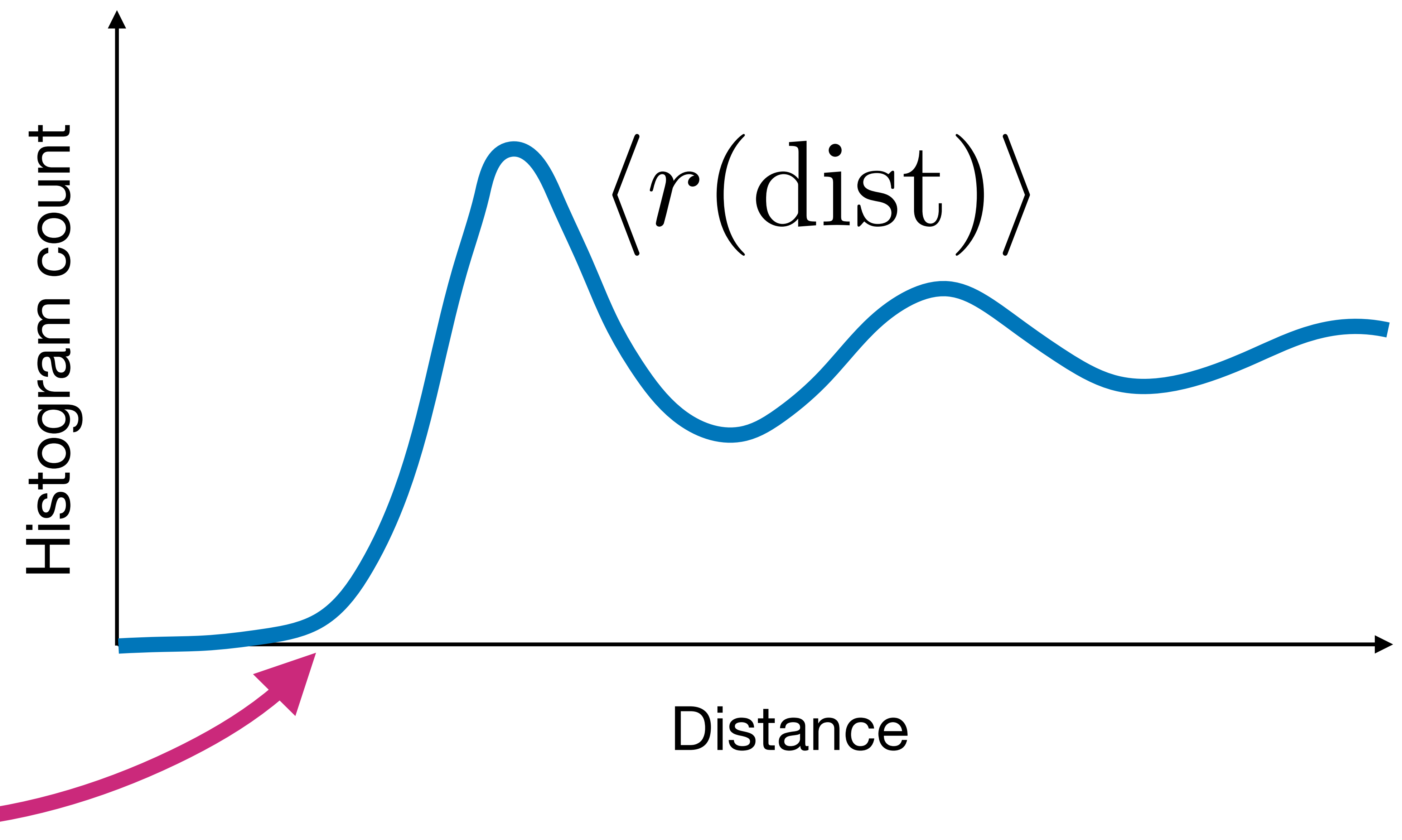




Loss Functions

PCF Loss at $i\text{-th}$ training iteration

$$L_{\mathrm{PCF}} = ||\langle r_i(\mathrm{dist})\rangle - \langle r(\mathrm{dist})\rangle||^2$$



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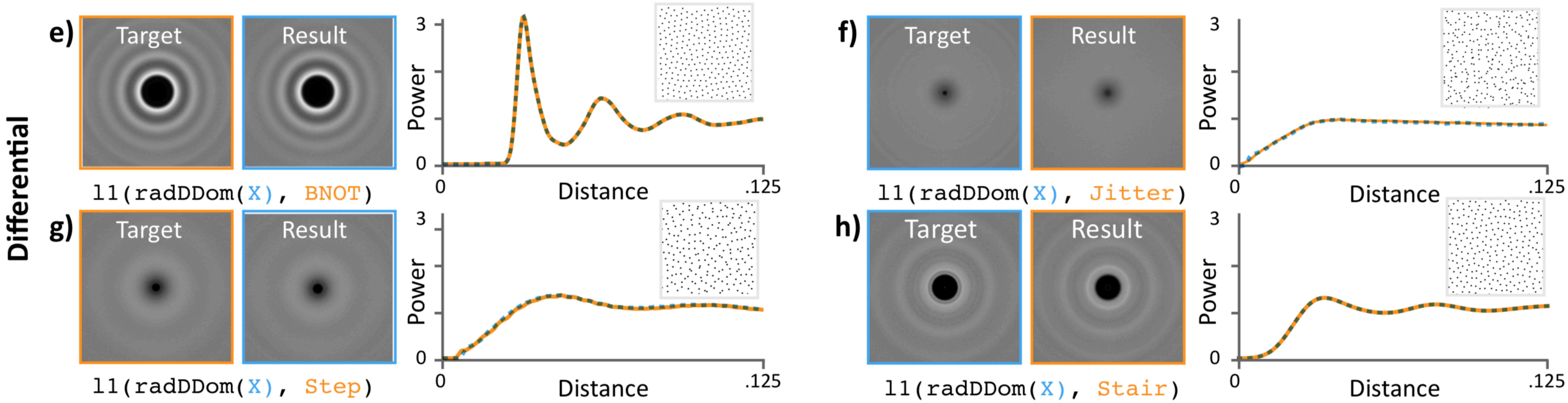
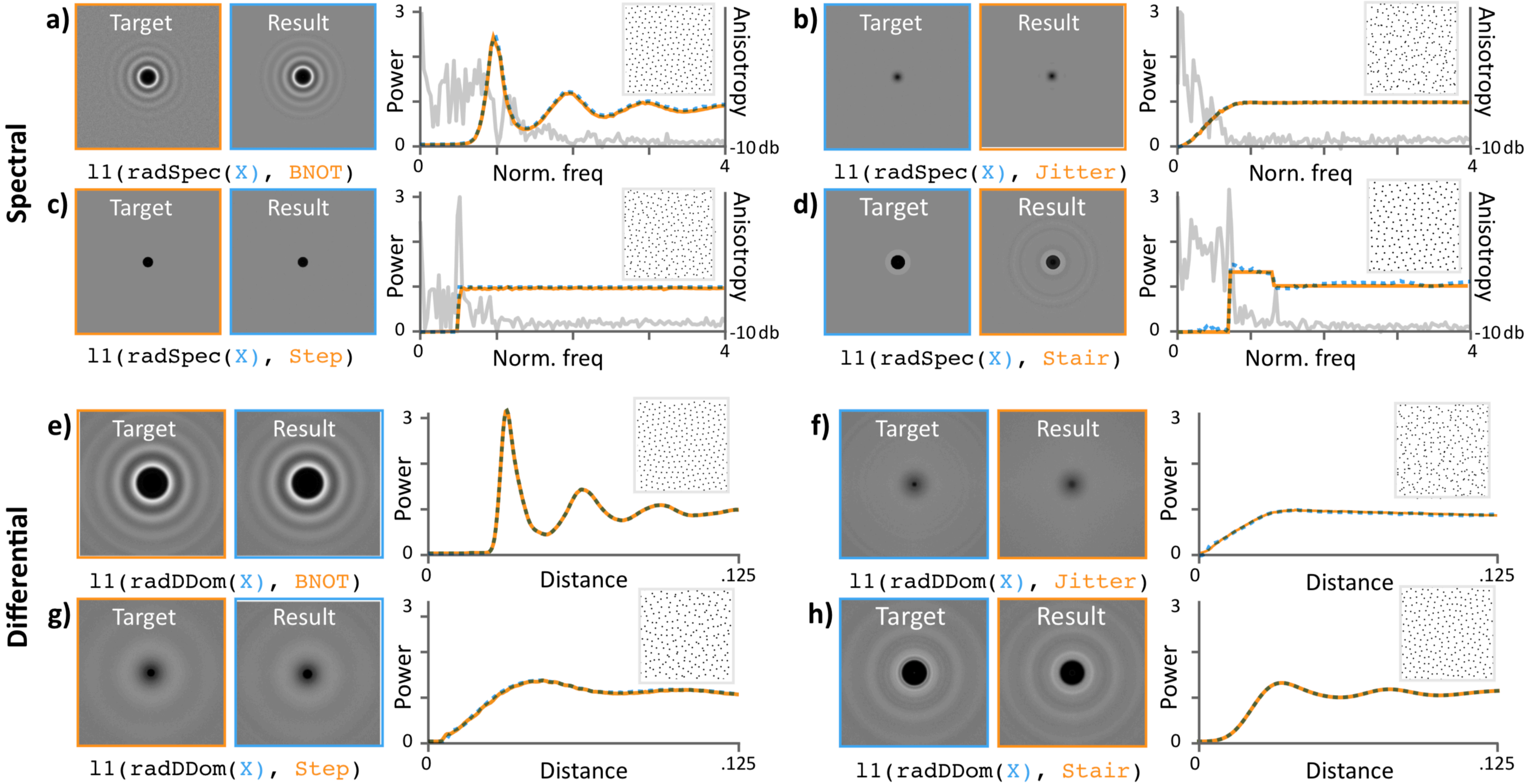
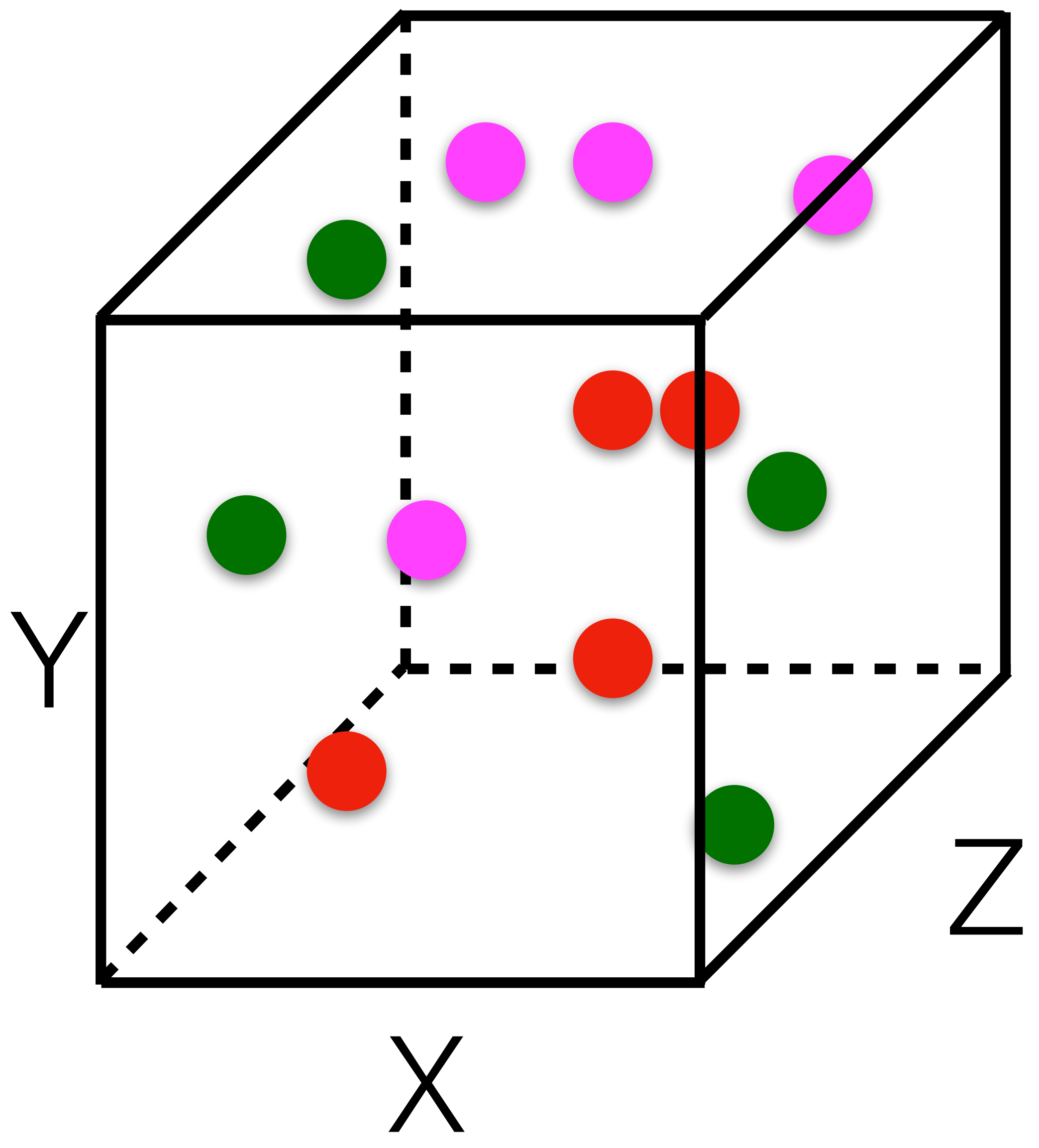
Spatial Target PCFs

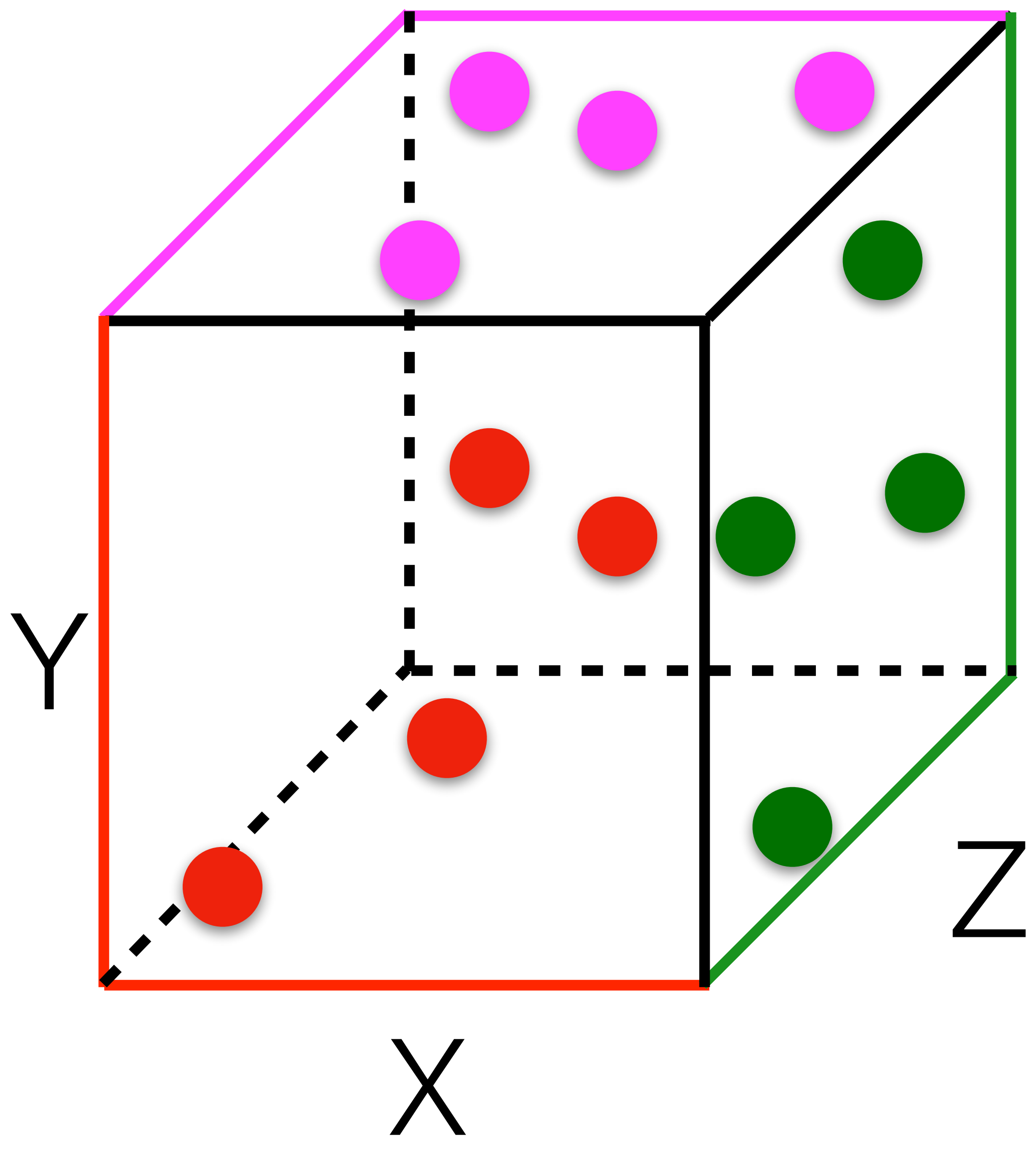


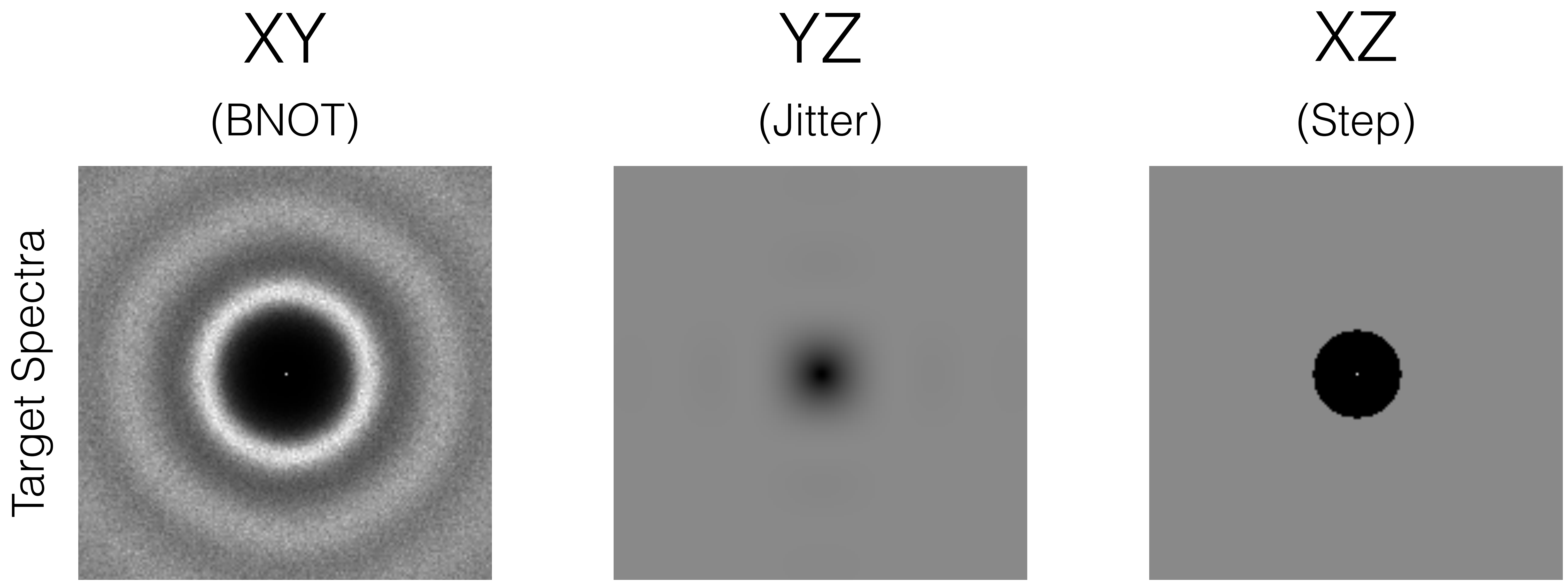

Spectral
a)
Target
Result
Power
Anisotropy
-10 db
Norm. freq
l1(radSpec(X), BNOT)
b)
Target
Result
Norn. freq
l1(radSpec(X), Jitter)
c)
l1(radSpec(X), Step)
d)
l1(radSpec(X), Stair)
Differential
e)
Distance
l1(radDDom(X), BNOT)
f)
l1(radDDom(X), Jitter)
g)
l1(radDDom(X), Step)
h)
l1(radDDom(X), Stair)

3D Point Samples (Different Projection Targets)

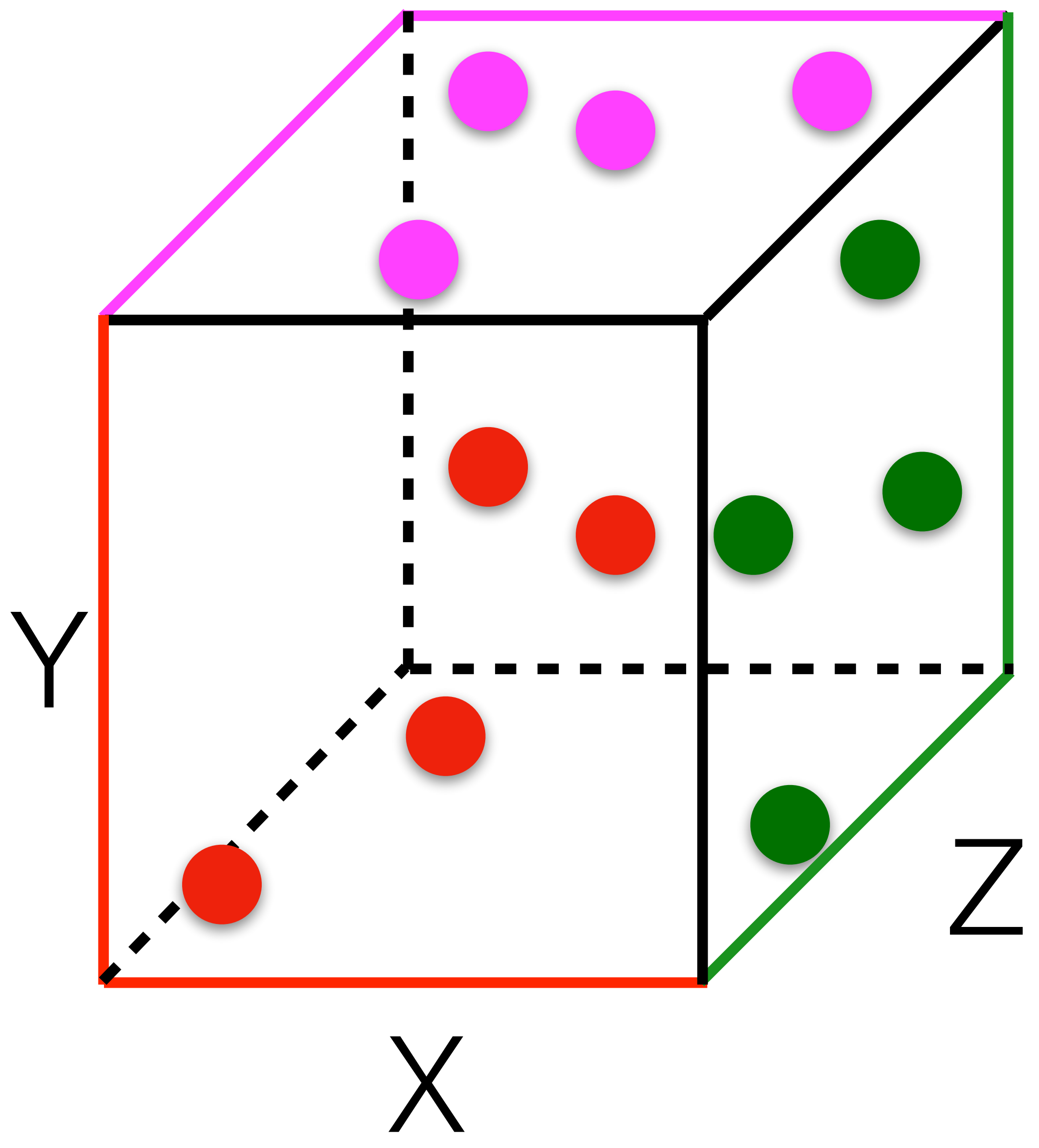


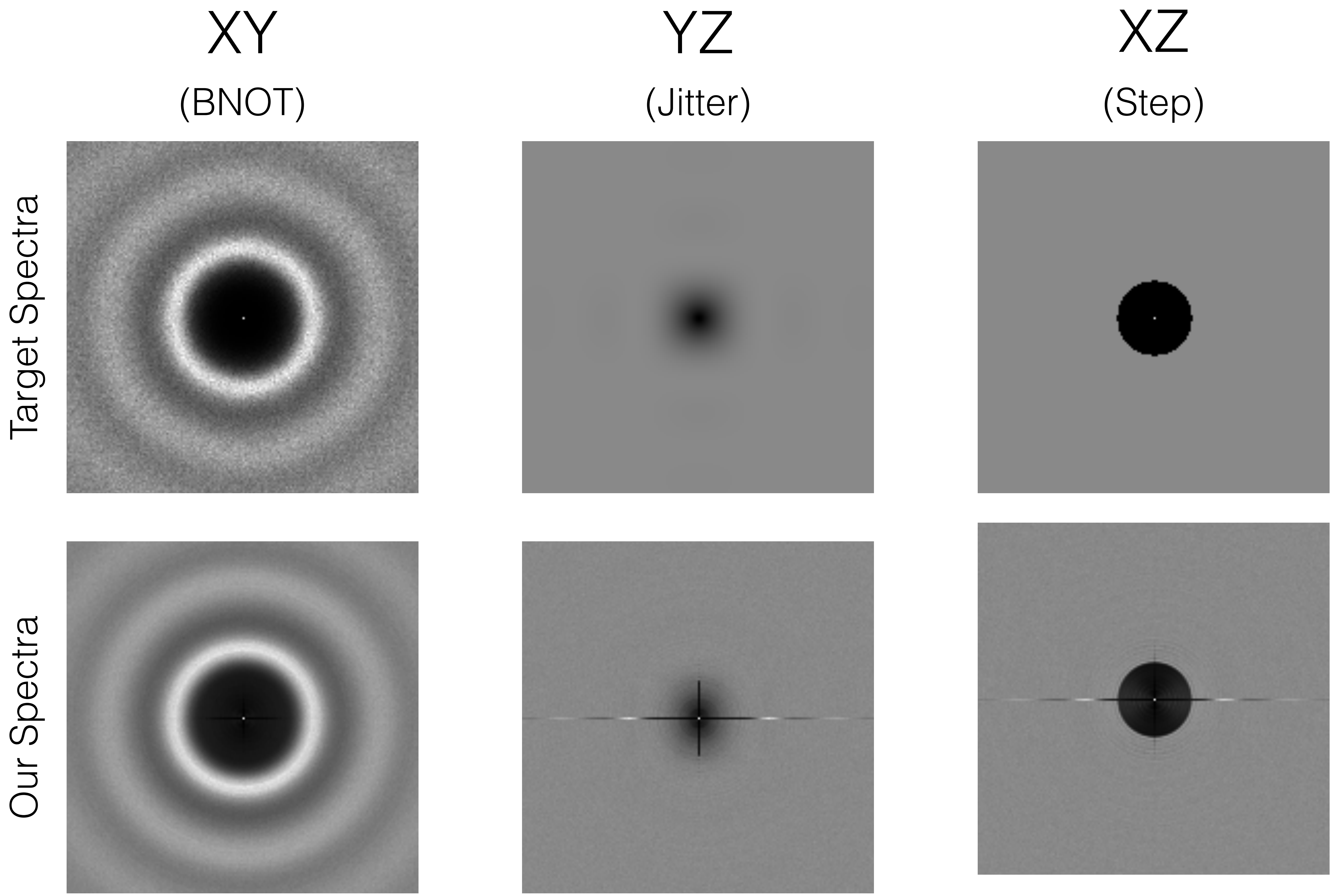
3D Point Samples (Different Projection Targets)



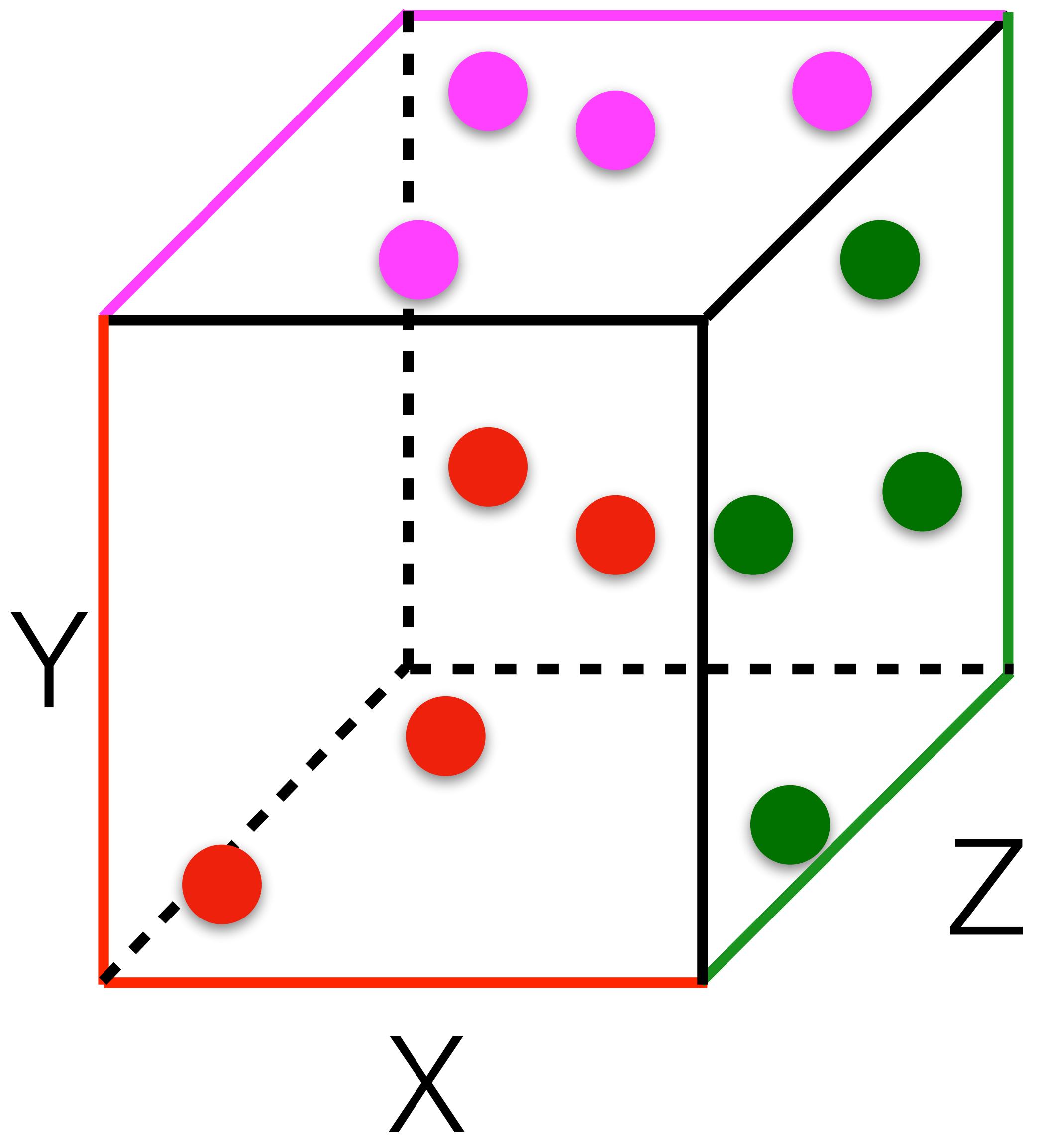


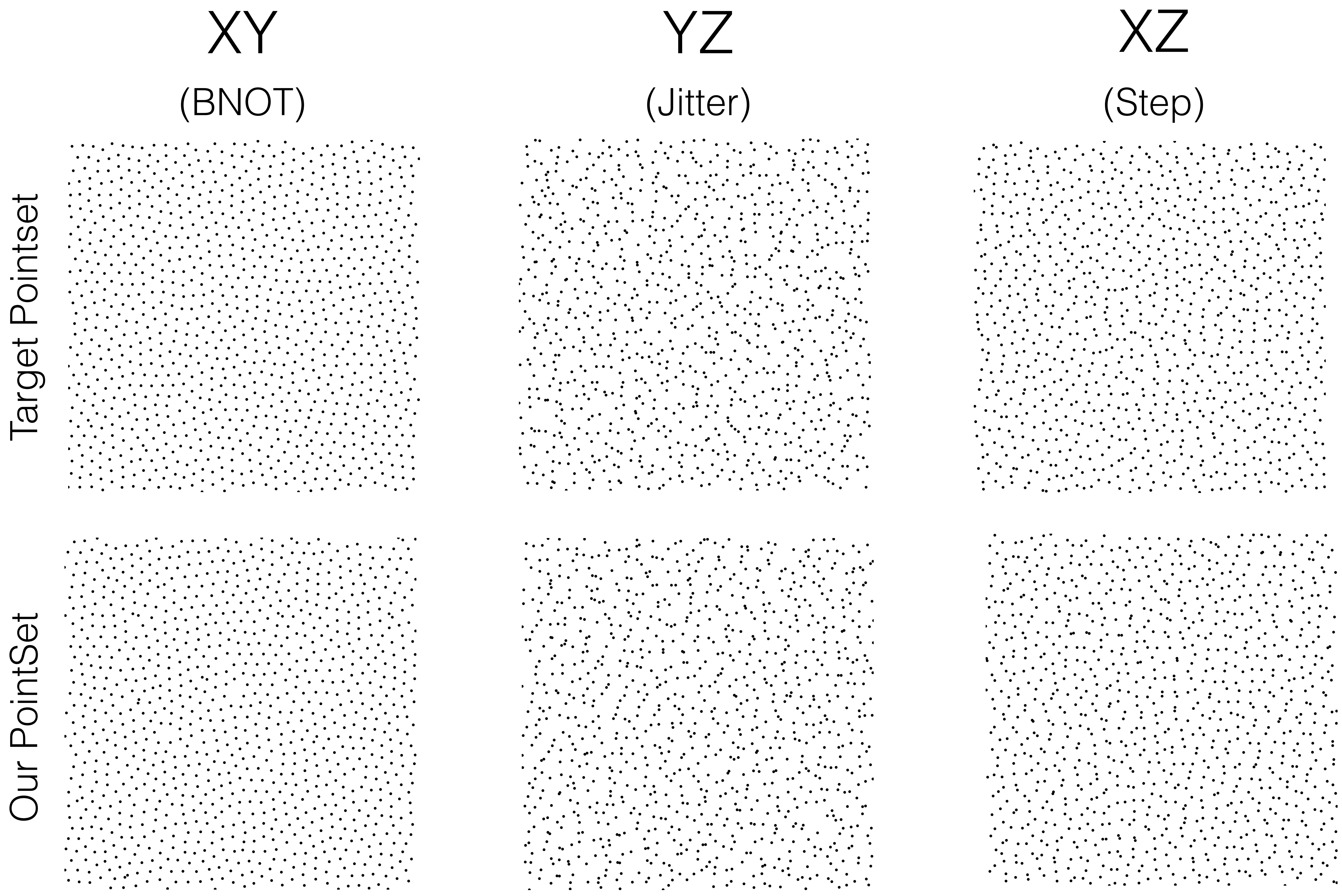
3D Point Samples (Different Projection Targets)





Point set: Projections are Preserved

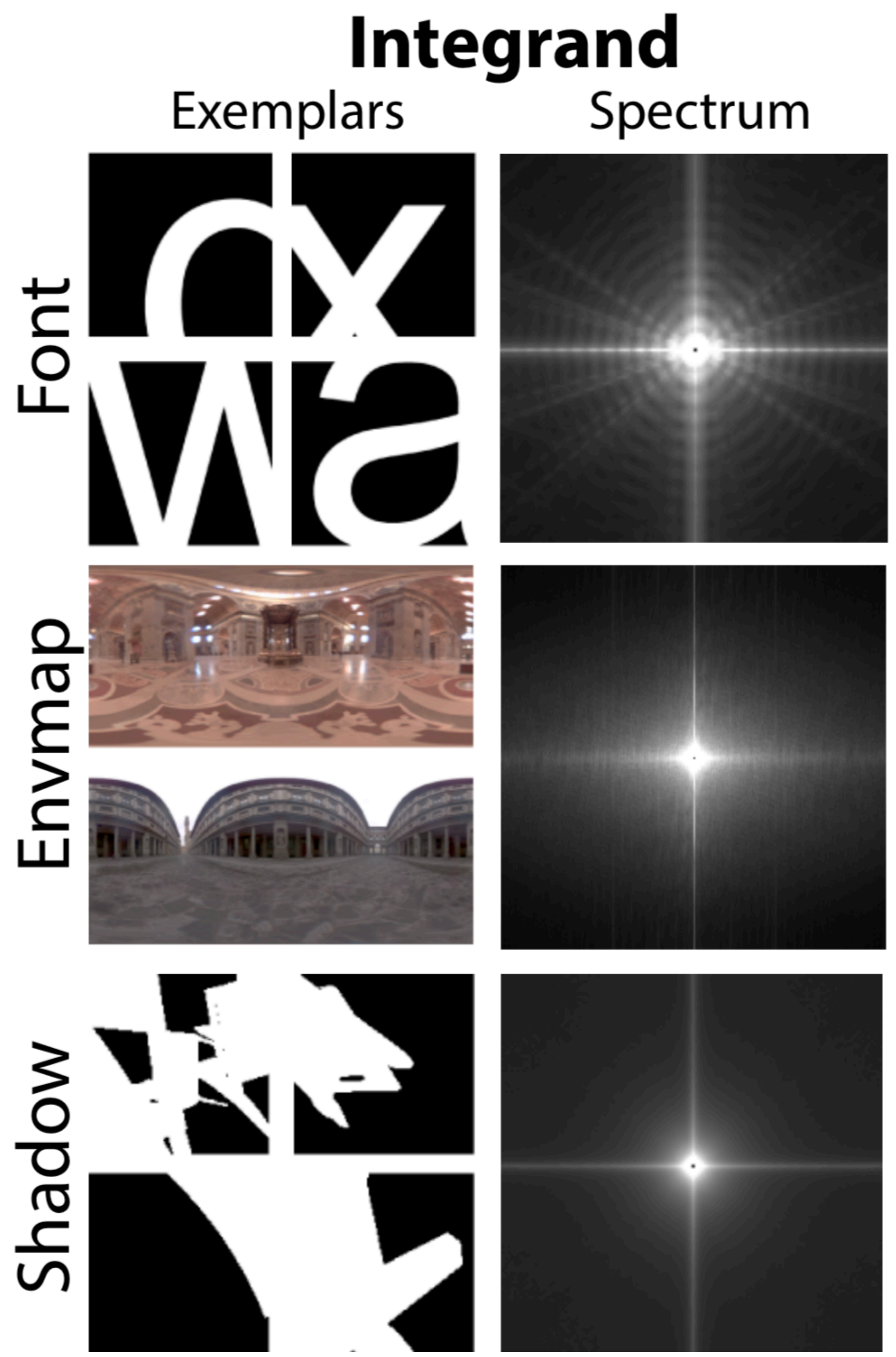




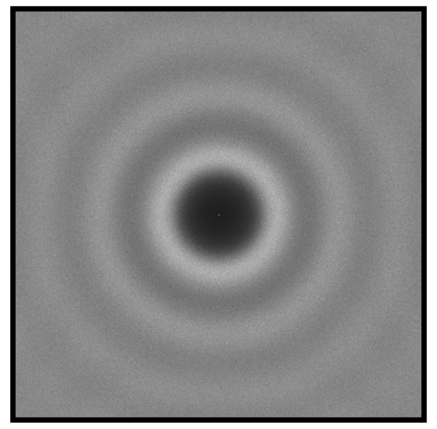
Novel Sampling Patterns

Leimkuhler et al. [SIGGRAPH Asia 2019]

Novel Sampling Patterns



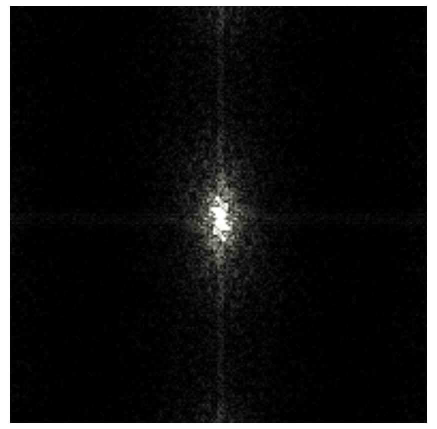
$$\mathrm{Var}(I_N) = \sum_{\Omega}$$



Sampling
Power spectrum

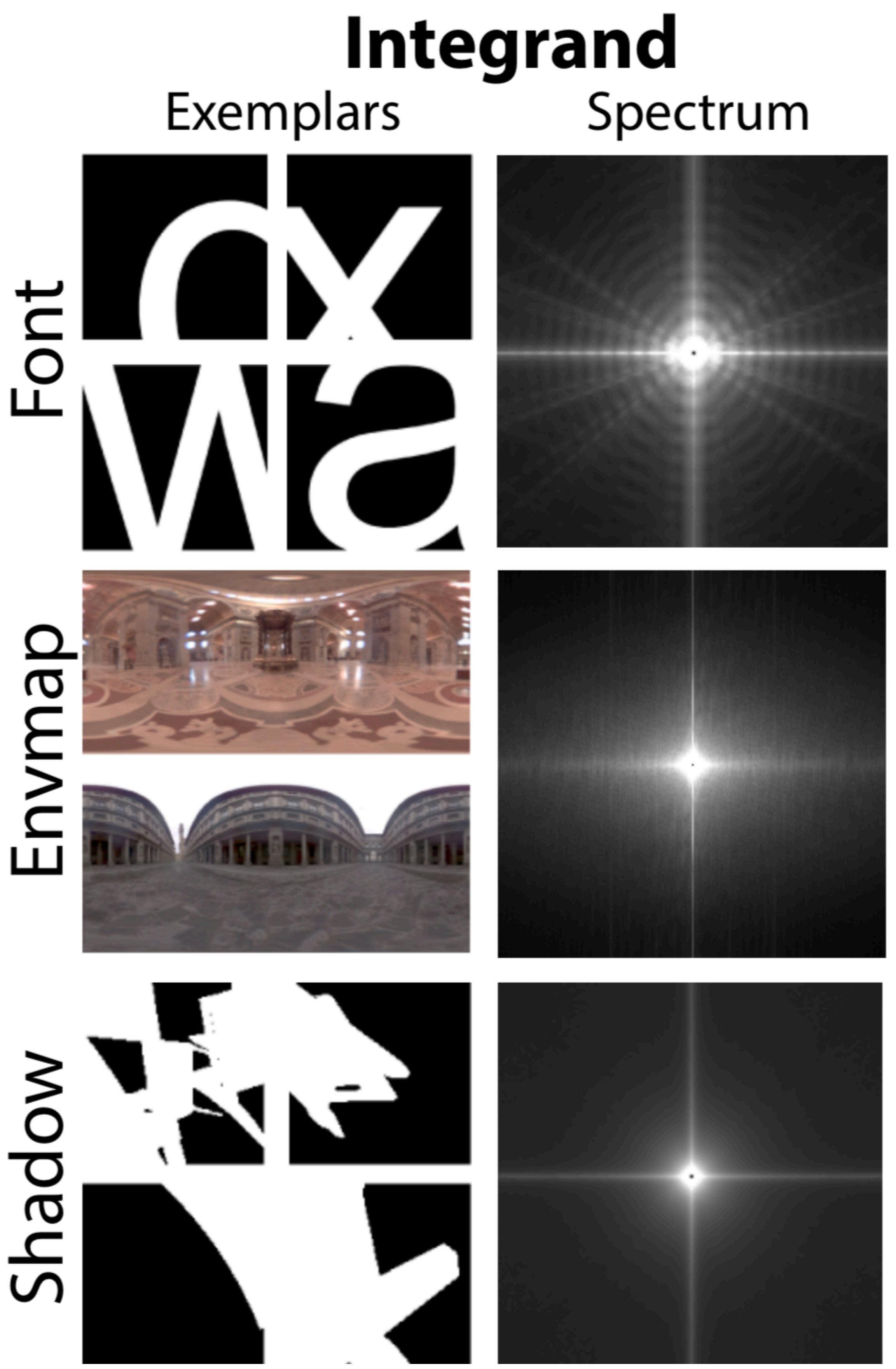
$\times$

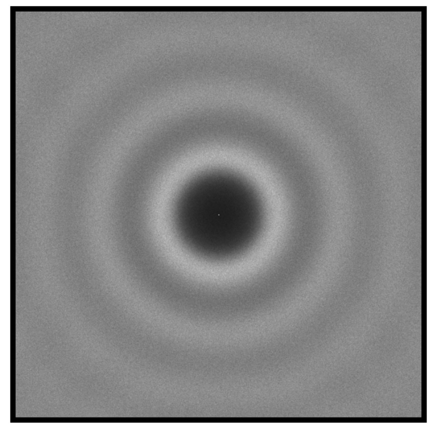
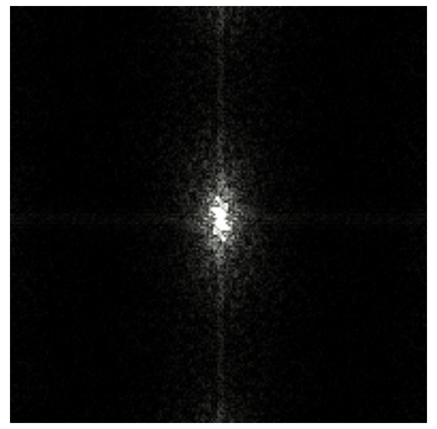
Integrand
Power spectrum

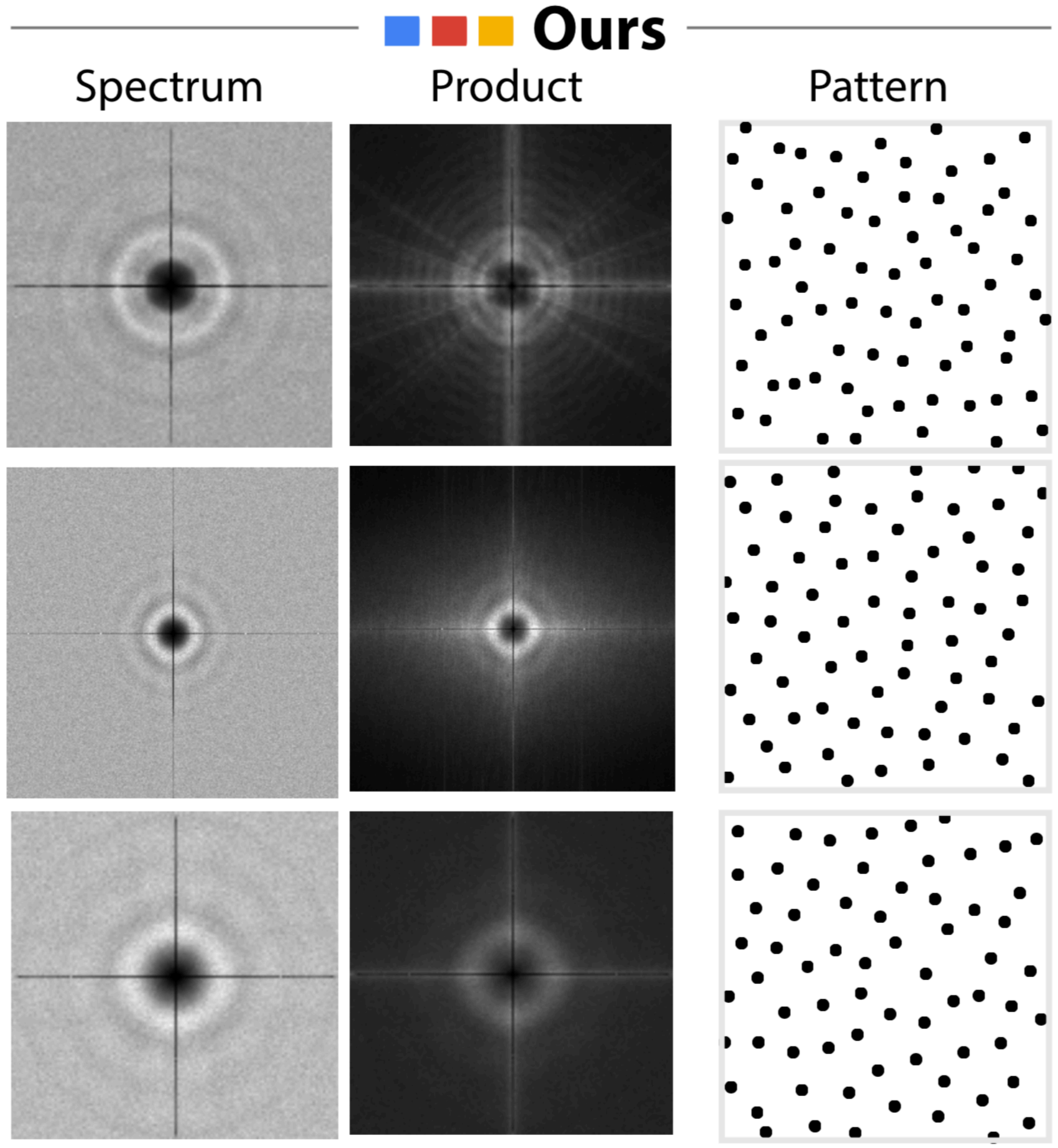


Leimkuhler et al. [SIGGRAPH Asia 2019]

Novel Sampling Patterns

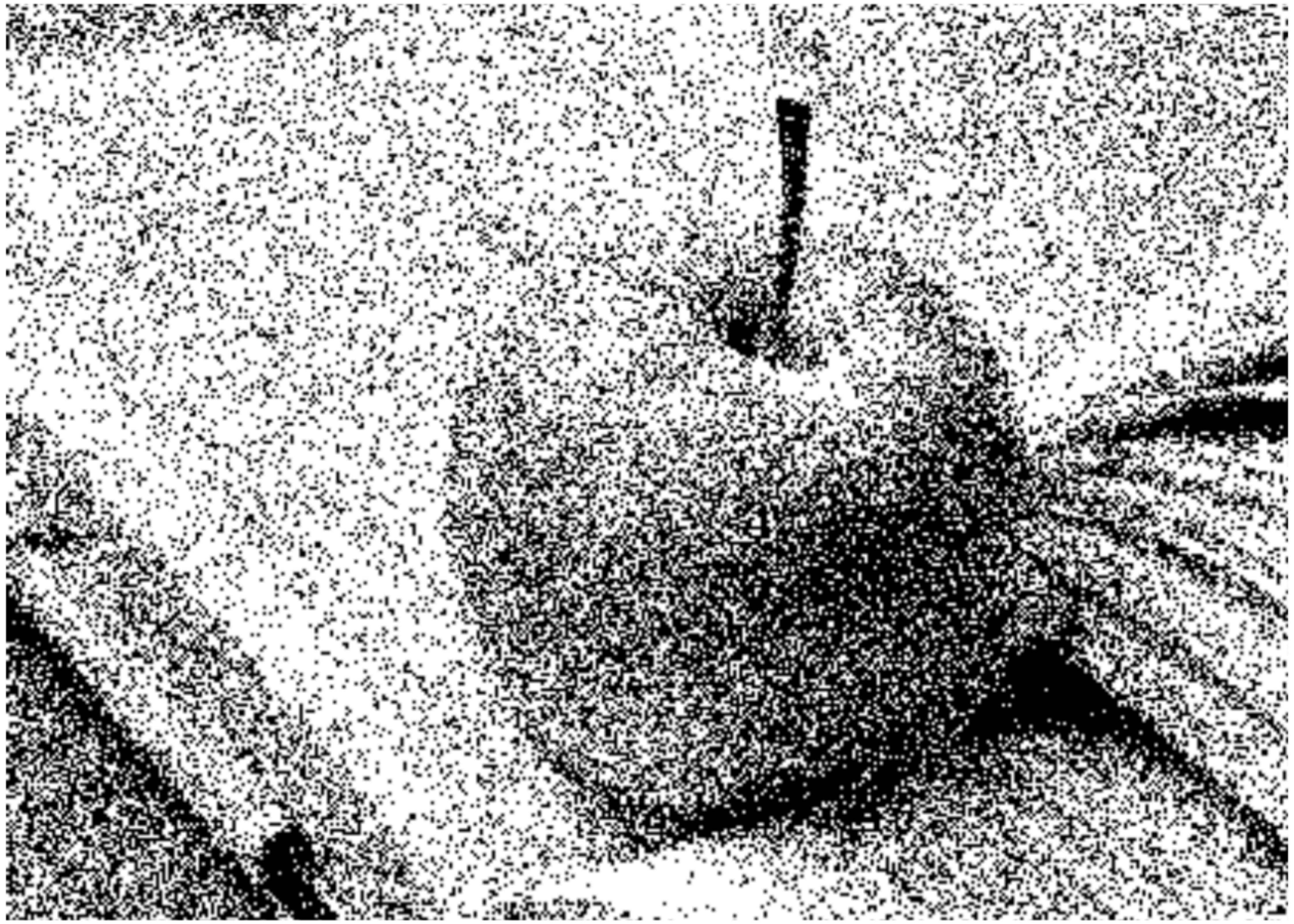


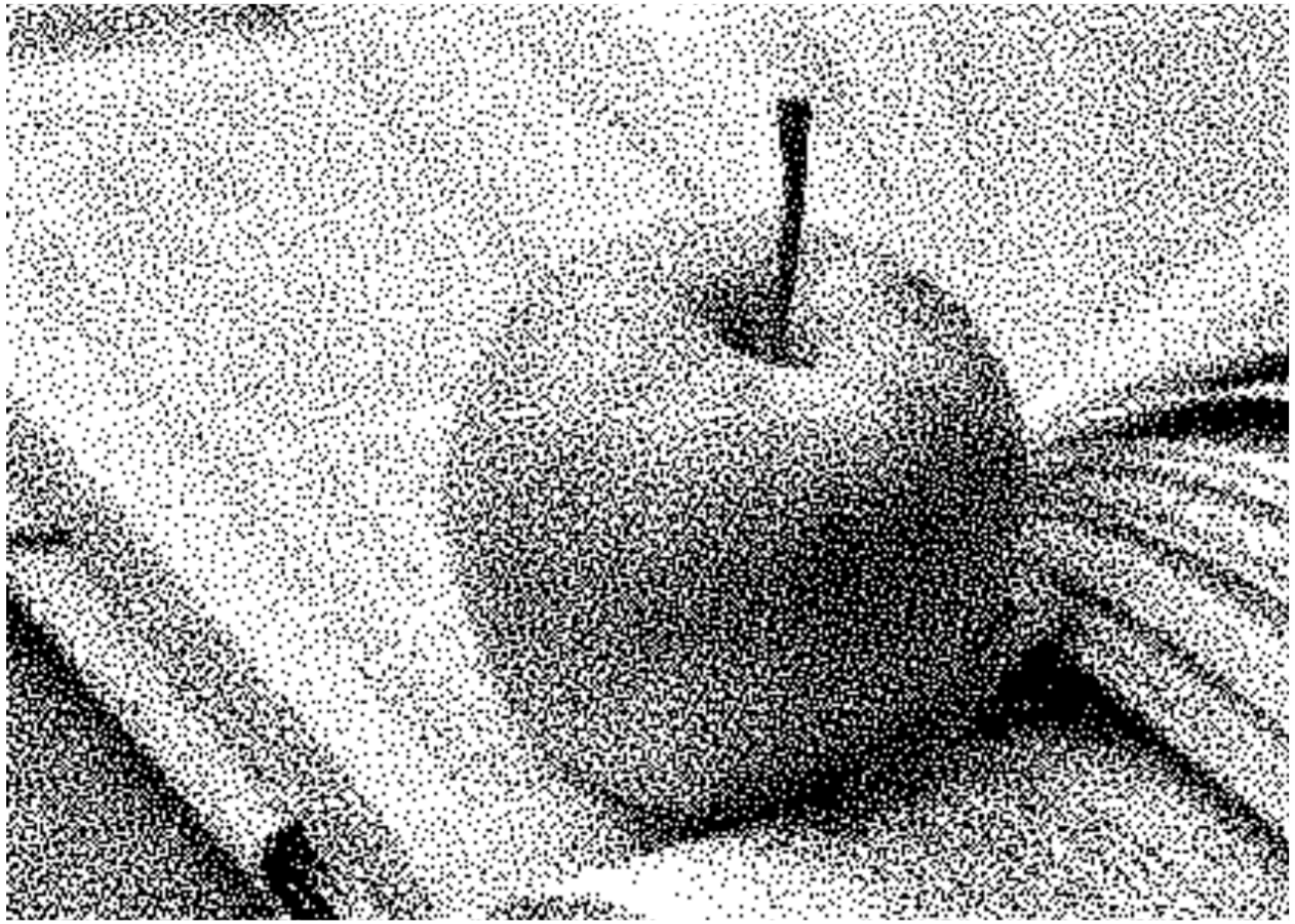
$\mathrm{Var}(I_N) = \sum_{\Omega}$  $\times$ 



Leimkuhler et al. [SIGGRAPH Asia 2019]

Blue Noise Dithering

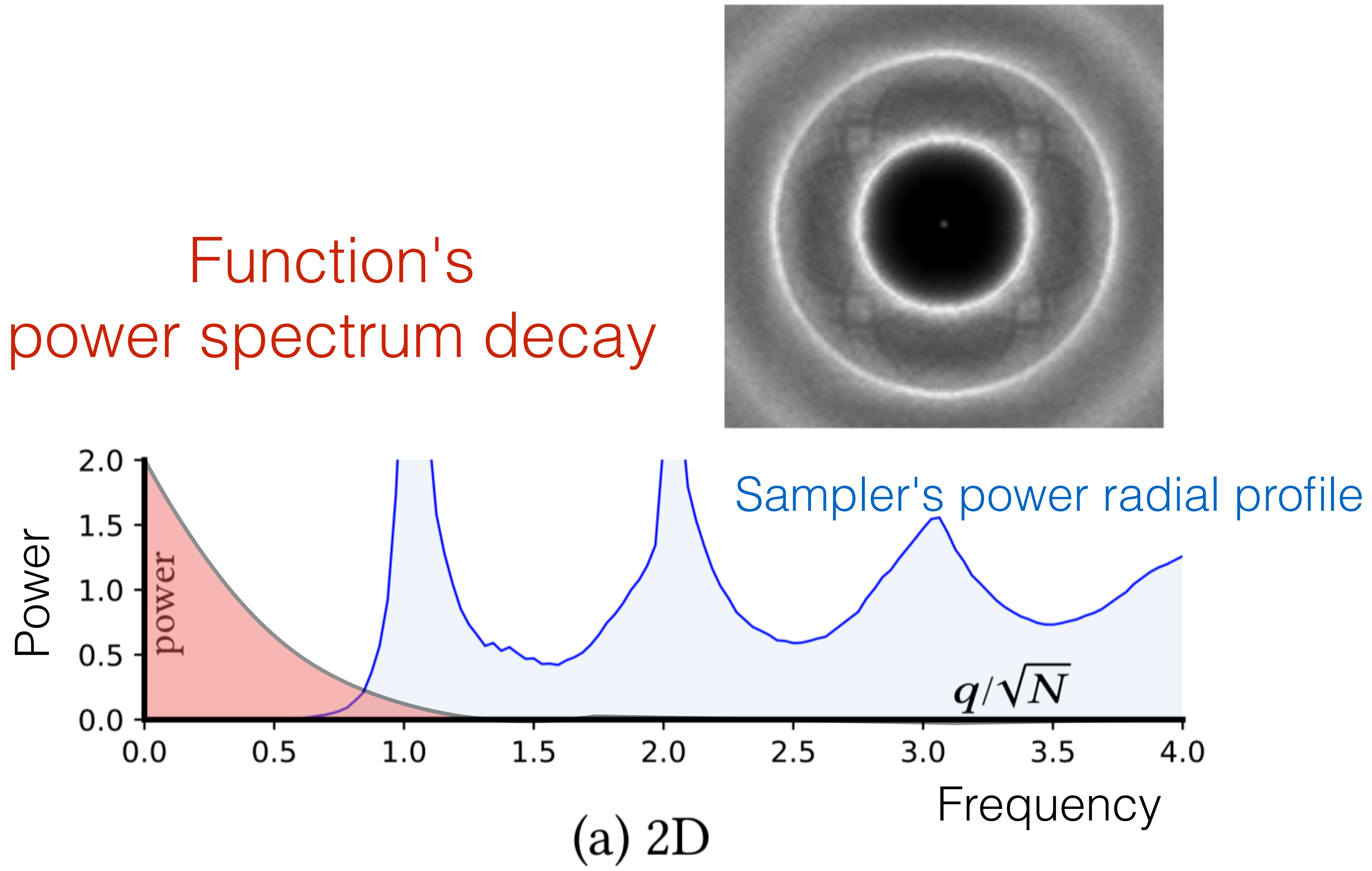




Leimkuhler et al. [SIGGRAPH Asia 2019]

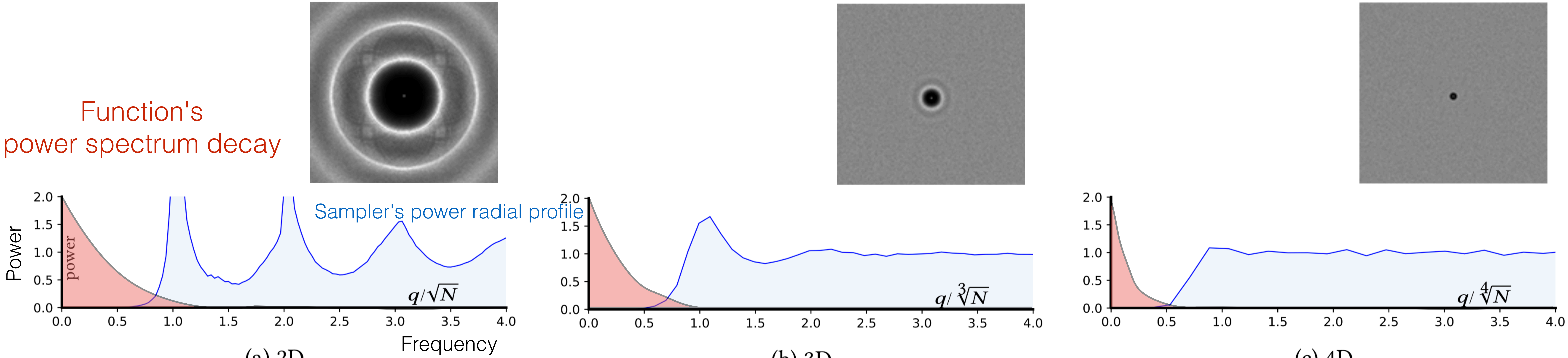
Novel Sampling Patterns

using radially averaged loss



Novel Sampling Patterns

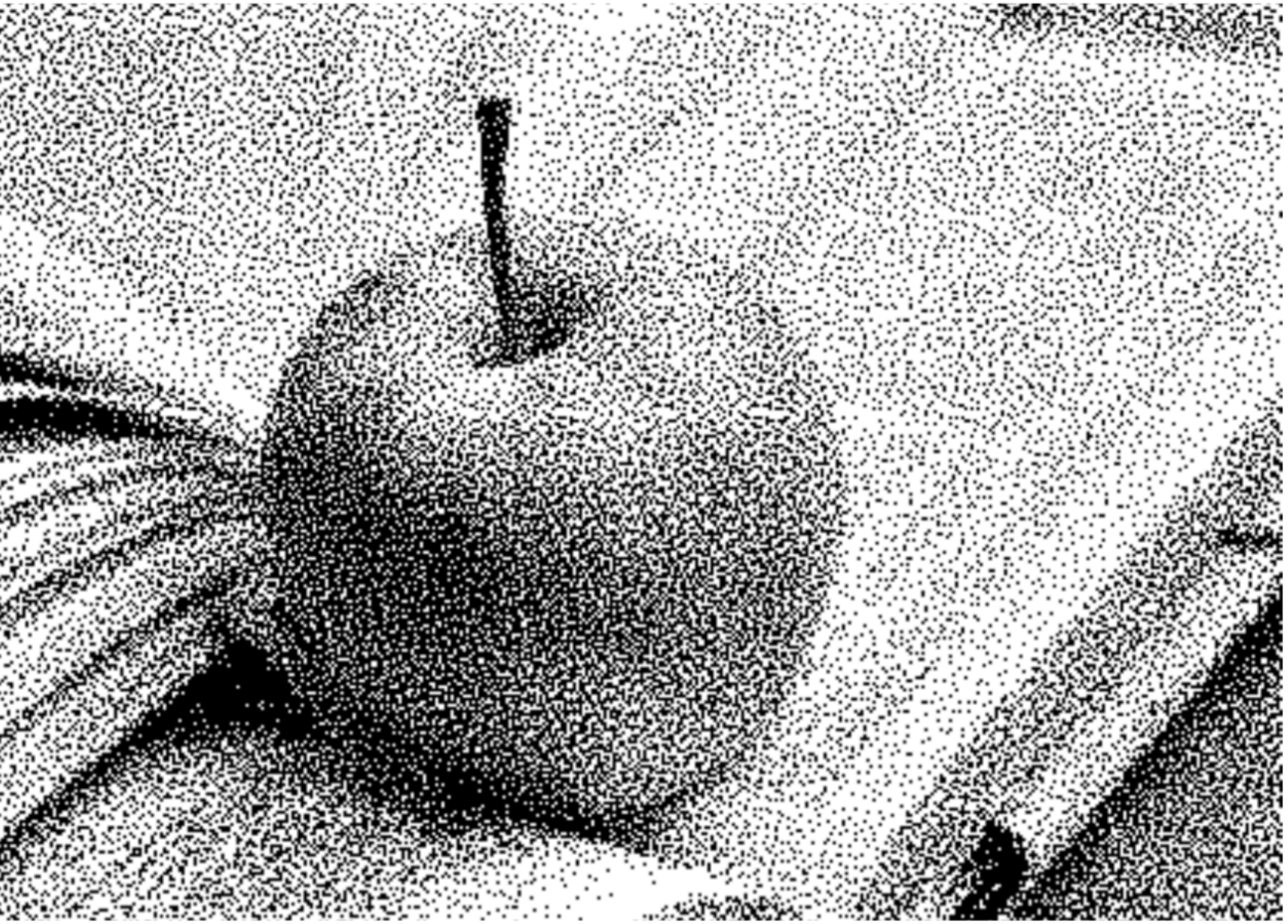
using radially averaged loss

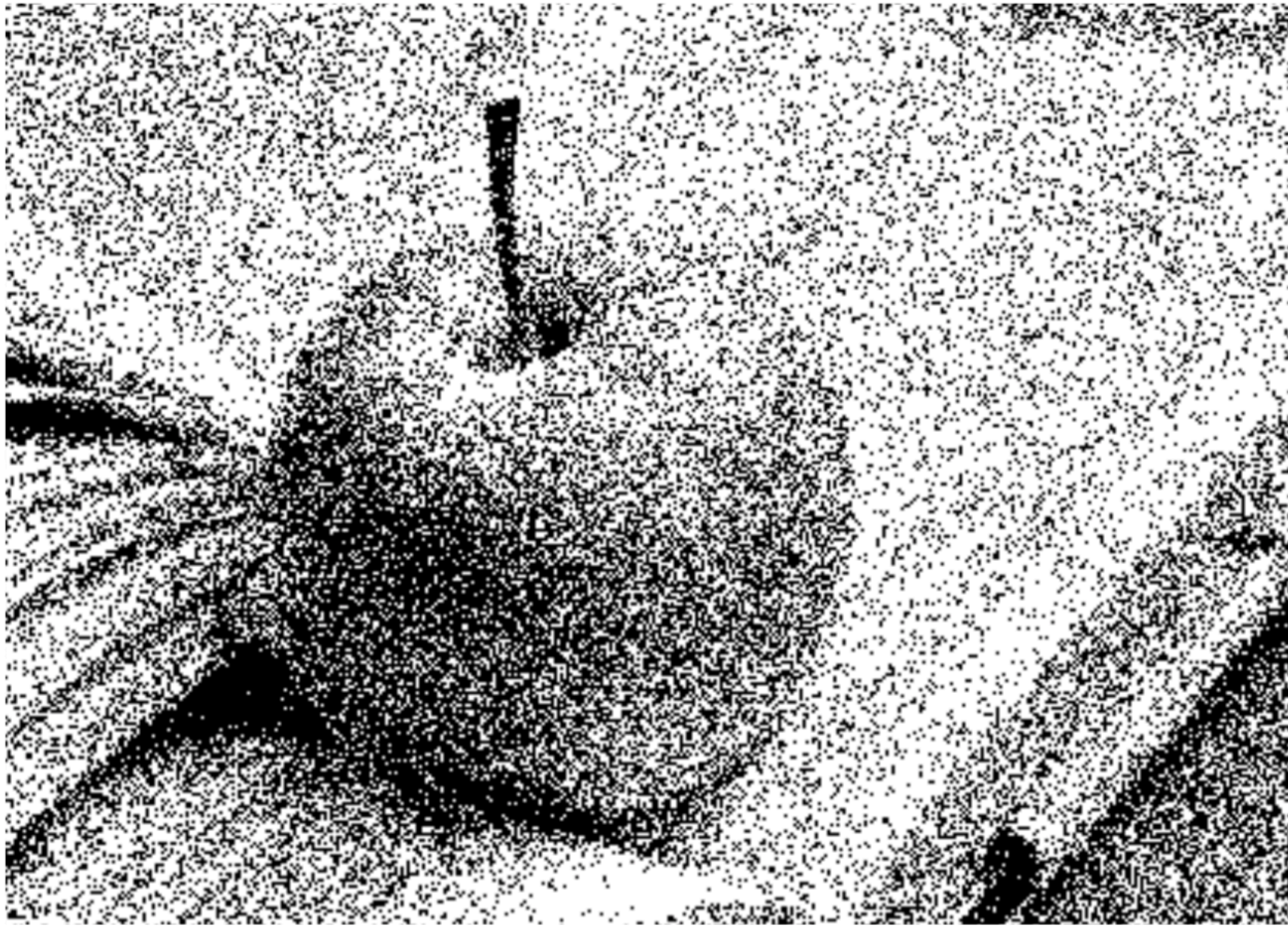


(a) 2D (b) 3D (c) 4D

using radially averaged loss

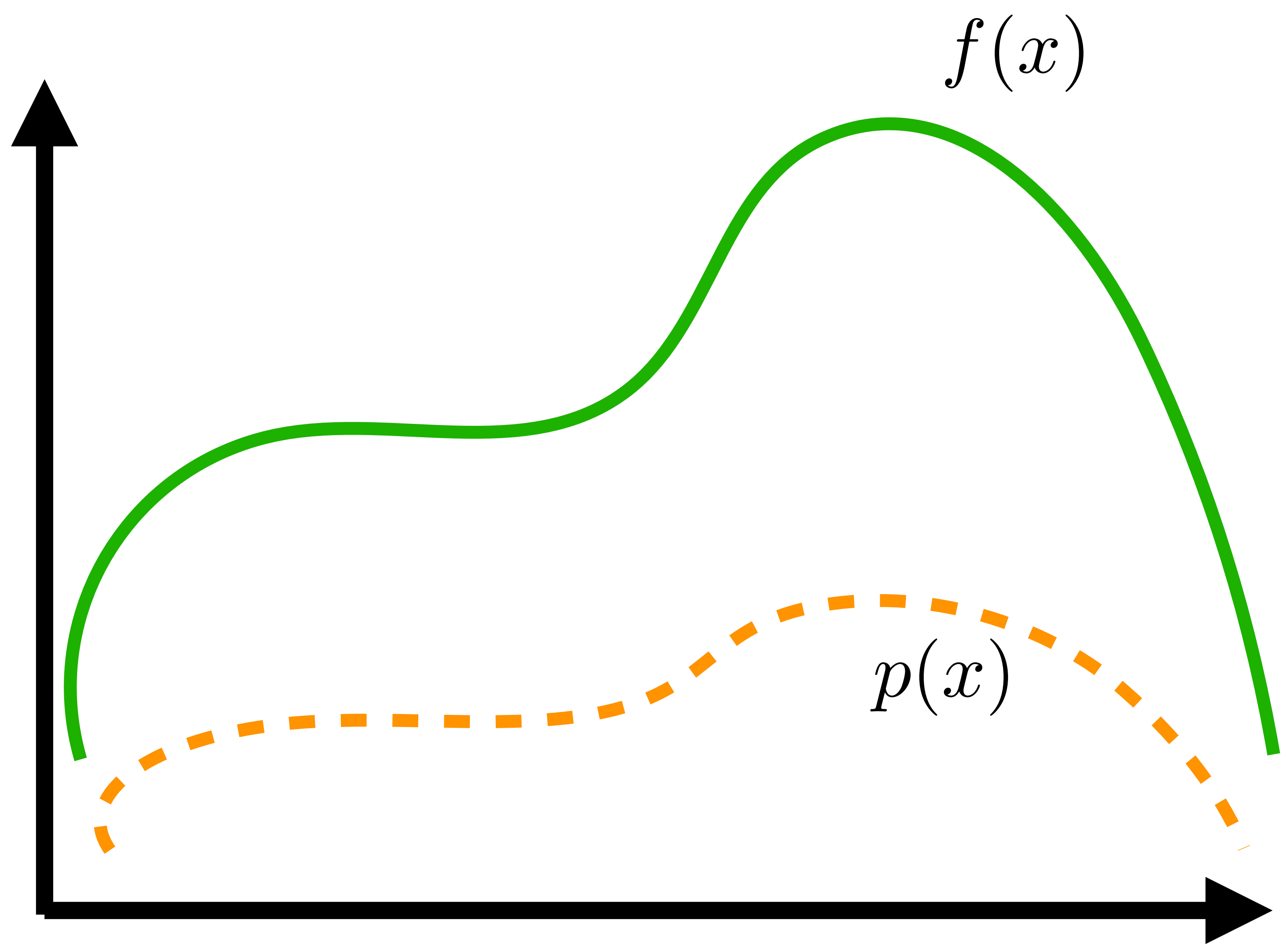
Blue Noise Dithering





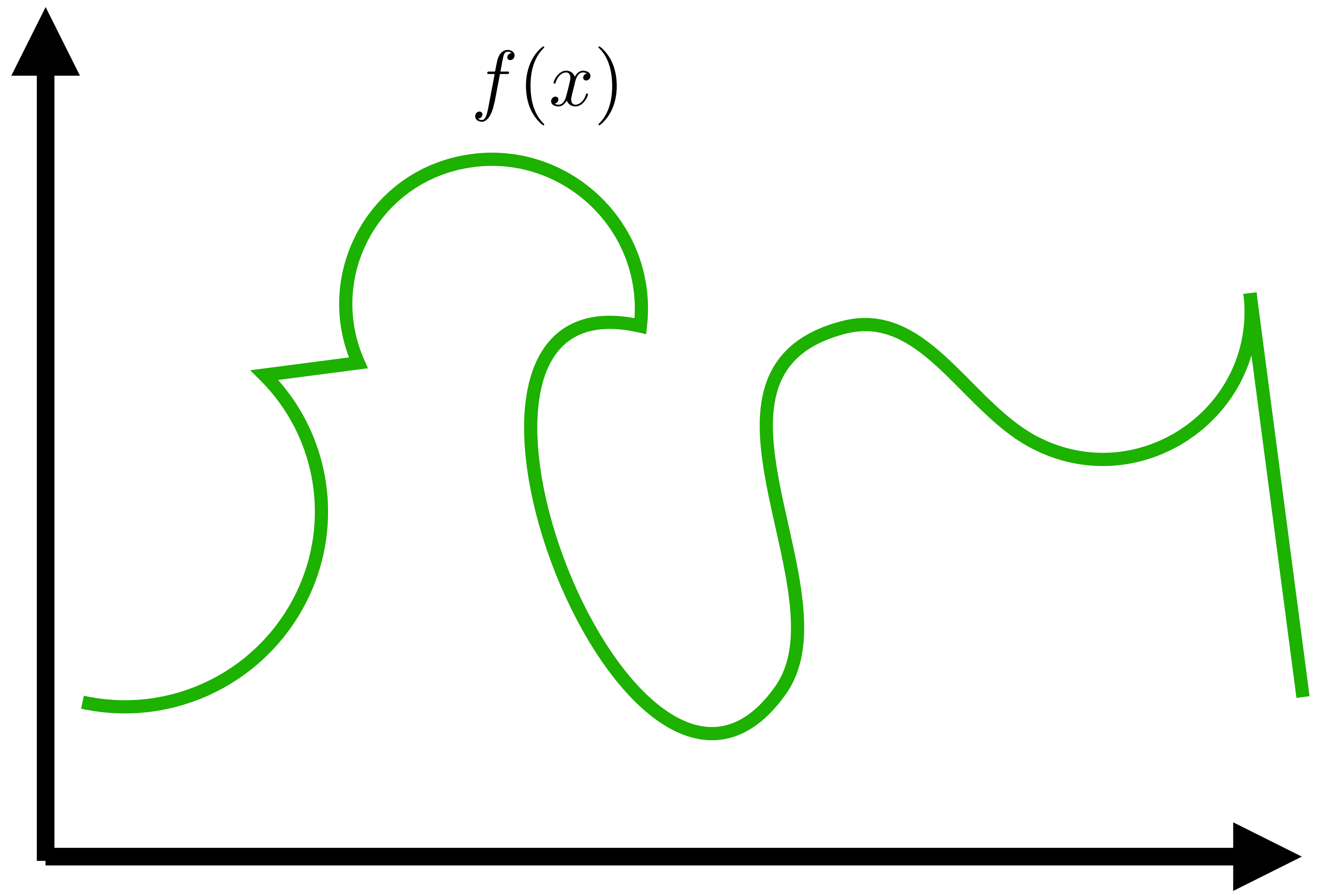
Normalizing Flows

Importance Sampling



$$I_N = \frac{1}{N} \sum_{k=1}^{N} \frac{f(x)}{p(x)}$$

Importance Sampling



$$I_N = \frac{1}{N}\sum_{k=1}^{N}\frac{f(x)}{p(x)}$$

$$p(x) = ???$$

Normalizing Flows

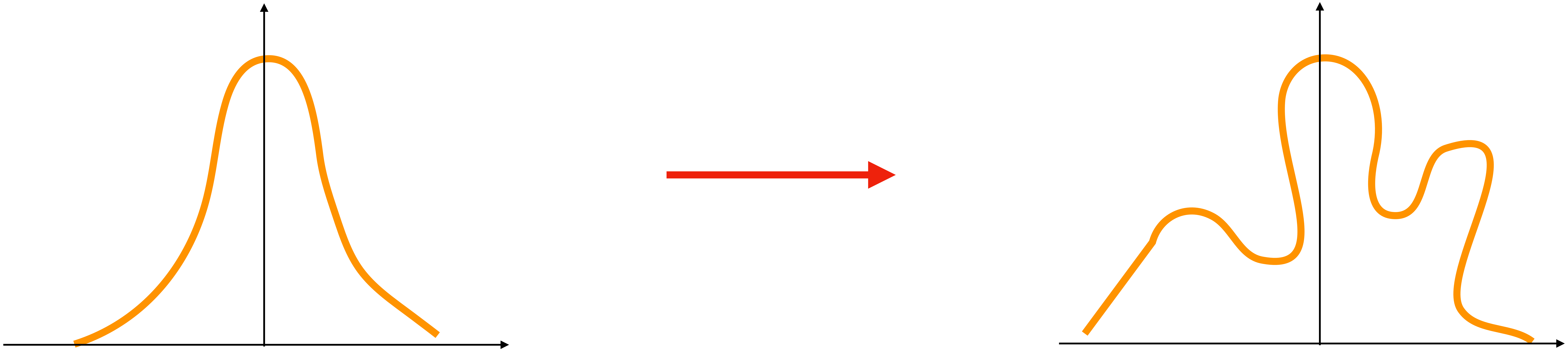
Normalizing Flows

Technique used in Machine learning to build complex probability distributions by transforming simple ones

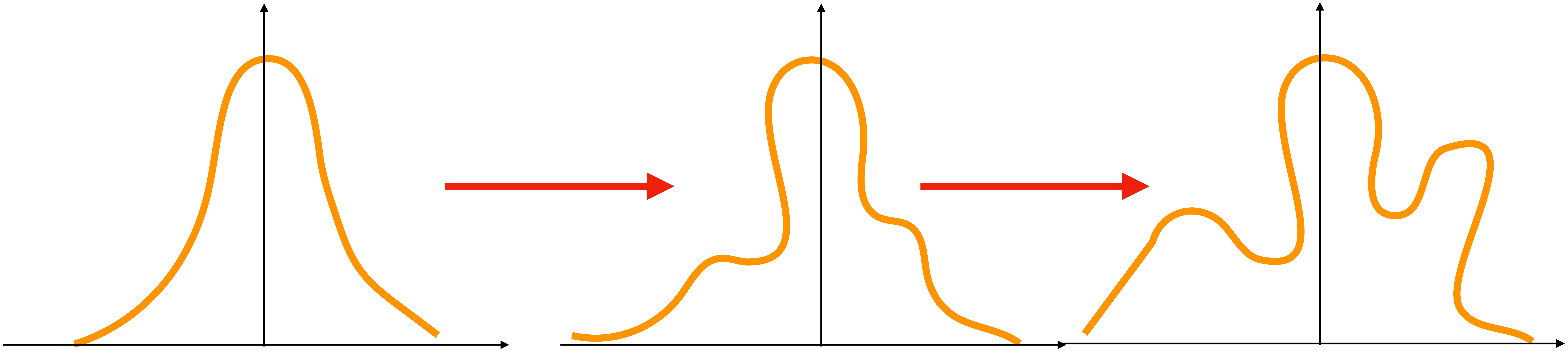
Used in the context of generative modeling

Generative modeling: learning without any target (unsupervised)

Complex Probability distributions from simple ones



Complex Probability distributions from simple ones



Normalizing Flows:
Basic mathematical framework

$z \sim p_\theta(z)$ Given a continuous variable with a distribution

$x = f_\theta(z) = f_k \circ \circ \circ f_2 \circ f_1(z)$ New distribution obtained

each f_i is invertible (bijective)

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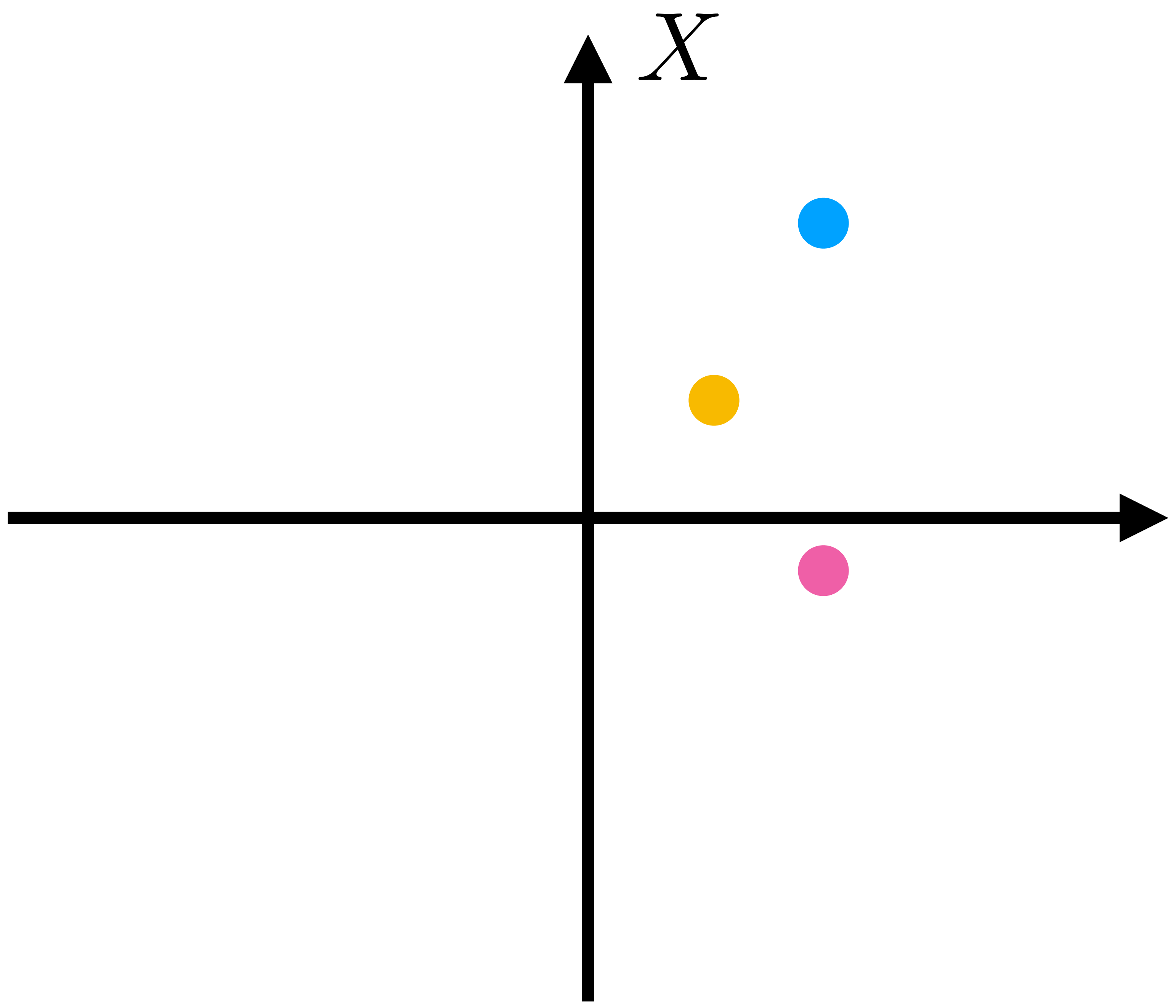
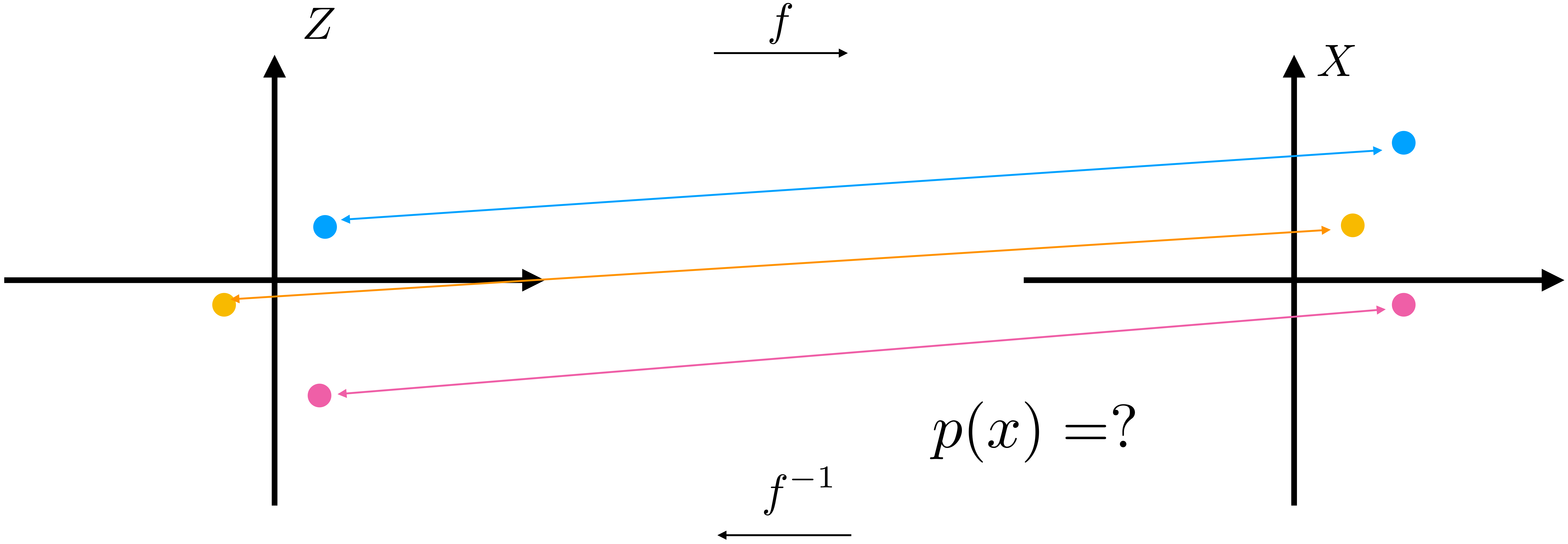
Distributions



Distributions



$$p(x) = ?$$

Distributions

$z \sim p_\theta(z)$ Given a continuous variable with a distribution

$$x = f_\theta(z) = f_k \circ \circ \circ f_2 \circ f_1(z)$$

each f_i is invertible (bijective)

$$p(x) = p(f^{-1}(x))$$

Change of Variables

$$f : Z \to X, f \text{ is invertible}$$
$$p(z) \text{ defined over } z \in Z$$

Change of variable formula says that:

$$p(x) = p(f^{-1}(x)) \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

Change of Variables

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

$$p(x) = p(f^{-1}(x)) \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

$$p(x) = p(z) \left| det \left(\frac{\partial z}{\partial x} \right) \right|$$

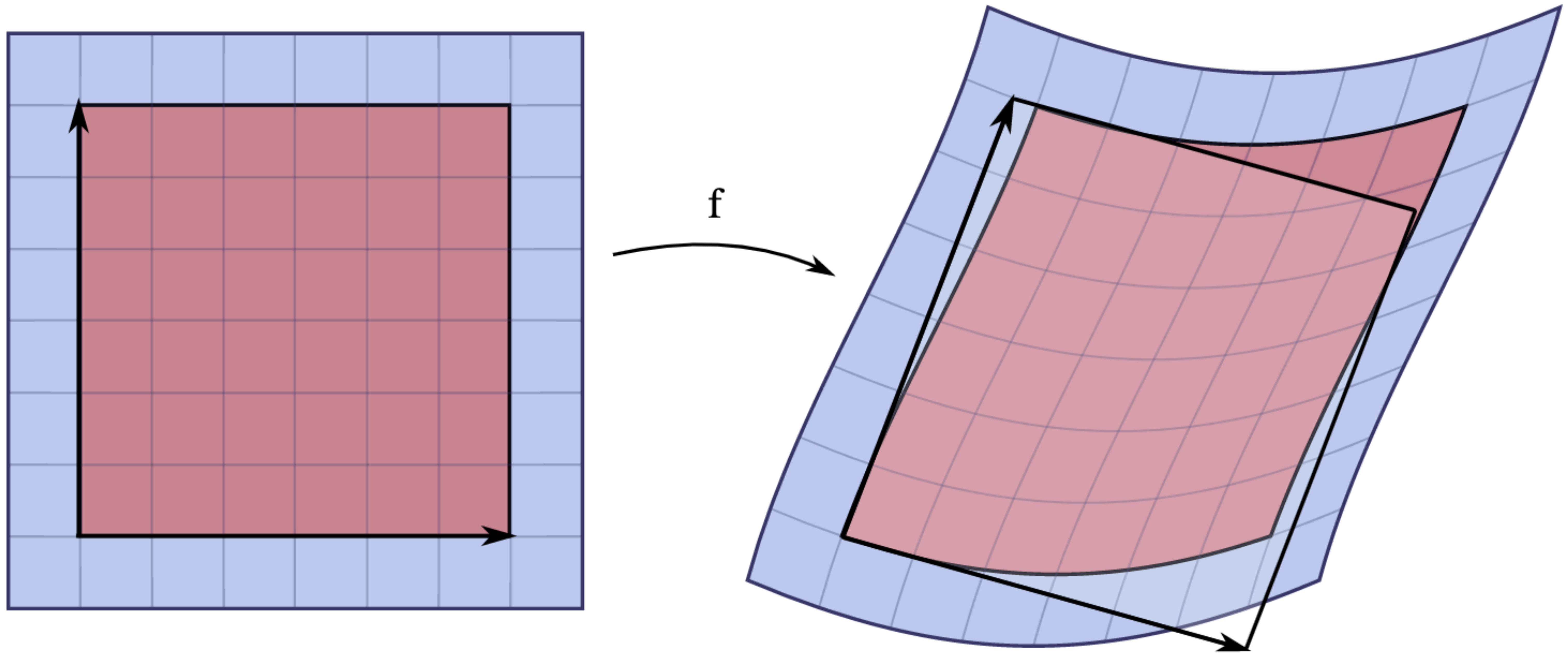
Jacobian Matrix

$$\mathbf{f} : \mathbb{R}^n \to \mathbb{R}^m$$

$$\mathbf{J} = \begin{bmatrix} \frac{\partial \mathbf{f}}{\partial x_1} & \cdots & \frac{\partial \mathbf{f}}{\partial x_n} \end{bmatrix} = \begin{bmatrix} \frac{\partial f_1}{\partial x_1} & \cdots & \frac{\partial f_1}{\partial x_n} \\ \vdots & \ddots & \vdots \\ \frac{\partial f_m}{\partial x_1} & \cdots & \frac{\partial f_m}{\partial x_n} \end{bmatrix}$$

Jacobian Matrix

$$\mathbf{f} : \mathbb{R}^2 \to \mathbb{R}^2$$



Jacobian determinant gives the ratio of the area of the approximating parallelogram to that of the original square.

Jacobian Matrix

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

$$p(x) = p(f^{-1}(x)) \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

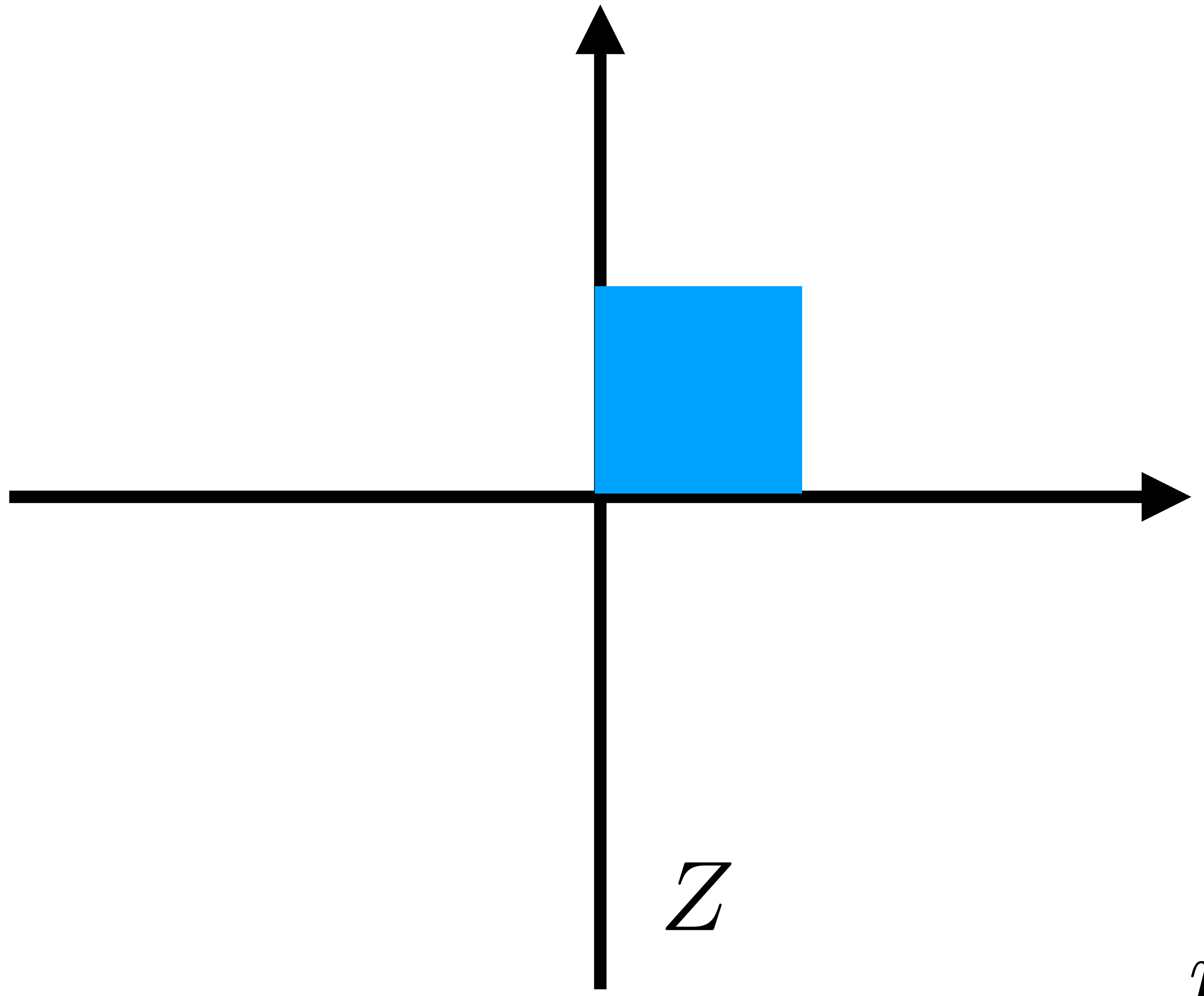
$$p(x) = p(z) \left| det \left(\frac{\partial z}{\partial x} \right) \right|$$

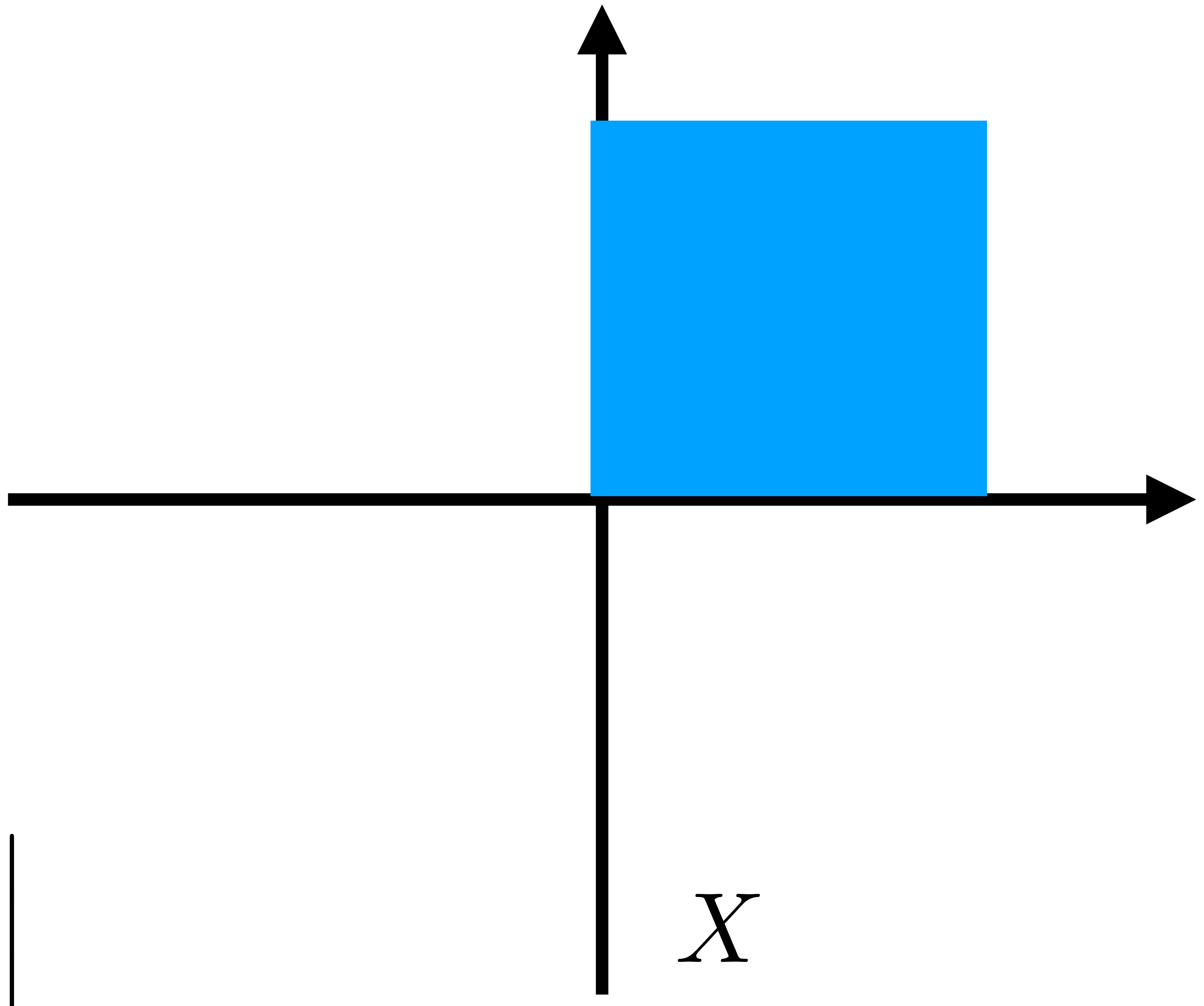
Invertible and Differentiable Mapping

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

$$det\left(\frac{\partial x}{\partial z}\right) = 4$$





$$p(x) = p(z) = \left| \frac{1}{det\left(\frac{\partial x}{\partial z}\right)} \right|$$

Maximize Log-likelihood

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

$$\log p(x) = \log p(z) + \log \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

Maximize Log-likelihood

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

$$\log p(x) = \log p(z) + \log \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

$$\log p(x) = \log p(z) + \sum_{i=1}^{K} \log \left| det \left(\frac{\partial f^{-1}(x)}{\partial x} \right) \right|$$

Jacobian: Lower Triangular Matrix

$f : Z \to X, f$ is invertible

$p(z)$ defined over $z \in Z$

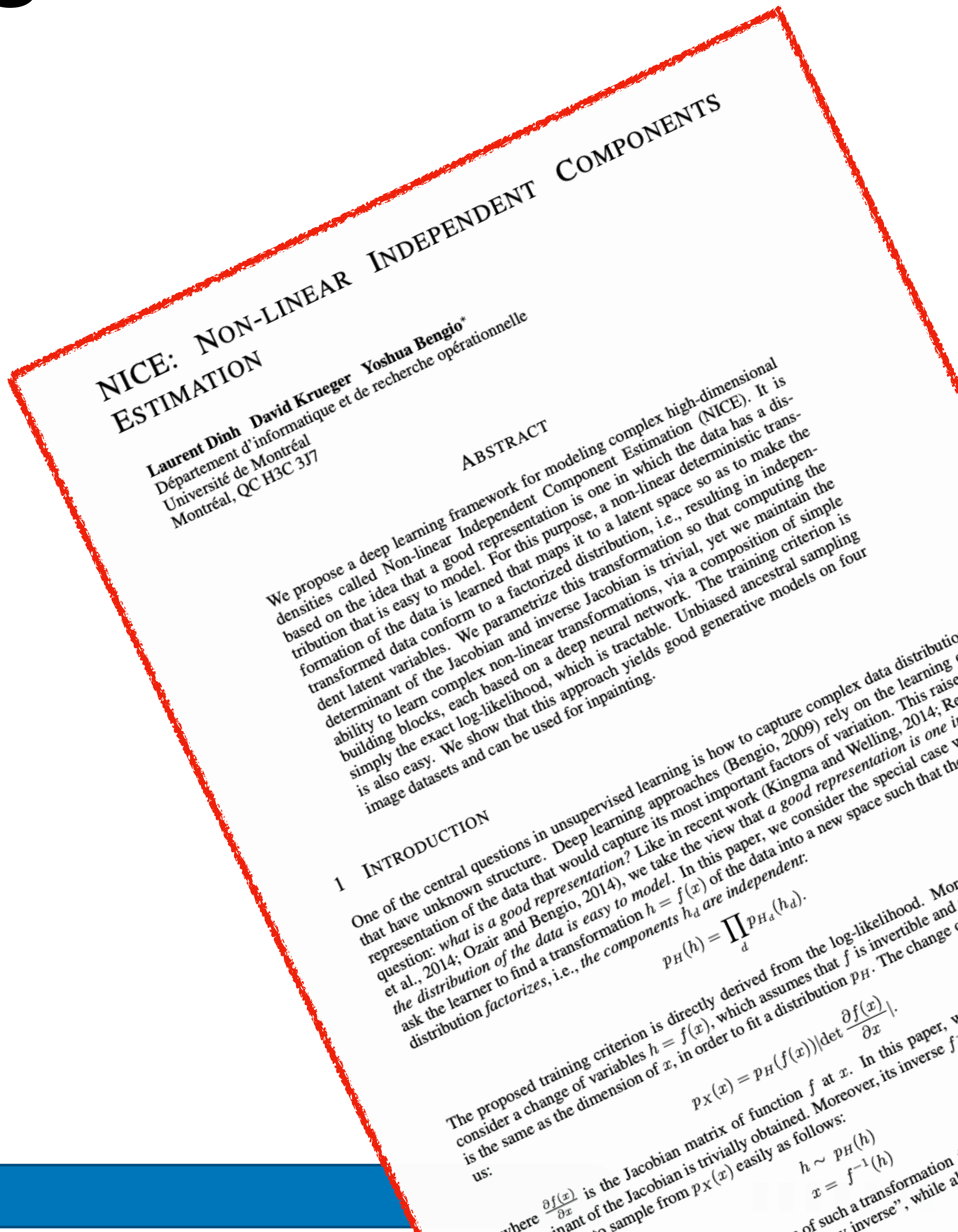
$$\mathbf{J} = \begin{bmatrix} \ell_{1,1} & & & & 0 \\ \ell_{2,1} & \ell_{2,2} & & & \\ \ell_{3,1} & \ell_{3,2} & \ddots & & \\ \vdots & \vdots & \ddots & \ddots & \\ \ell_{n,1} & \ell_{n,2} & \cdots & \ell_{n,n-1} & \ell_{n,n} \end{bmatrix}$$

How to ensure lower-triangular Jacobian matrix?

$$z \in \mathbb{R}^D$$

$$z_{1:d}$$

$$z_{d+1:D}$$



NICE: NON-LINEAR INDEPENDENT COMPONENTS ESTIMATION

Laurent Dinh David Krueger Yoshua Bengio*
Département d'informatique et de recherche opérationnelle
Université de Montréal
Montréal, QC H3C 3J7

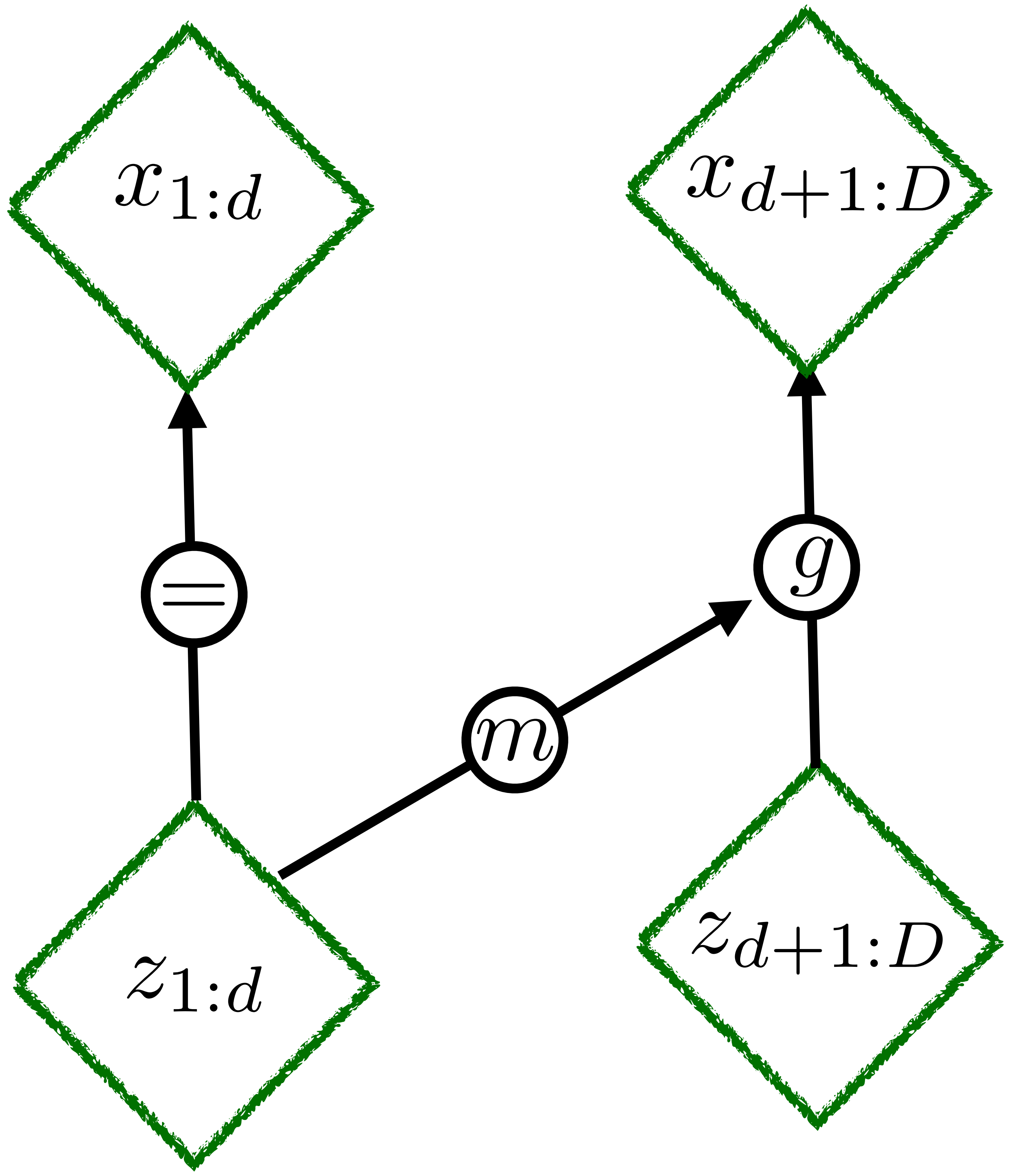
ABSTRACT

We propose a deep learning framework for modeling complex high-dimensional densities called Non-linear Independent Component Estimation (NICE). It is based on the idea that a good representation is one in which the data has a distribution that is easy to model. For this purpose, a non-linear deterministic transformation of the data is learned that maps it to a latent space so as to make the transformed data conform to a factorized distribution, i.e., resulting in independent latent variables. We parametrize this transformation so that computing the determinant of the Jacobian and inverse Jacobian is trivial, yet we maintain the ability to learn complex non-linear transformations, via a composition of simple building blocks, each based on a deep neural network. The training criterion is simply the exact log-likelihood, which is tractable. Unbiased ancestral sampling is also easy. We show that this approach yields good generative models on four image datasets and can be used for inpainting.

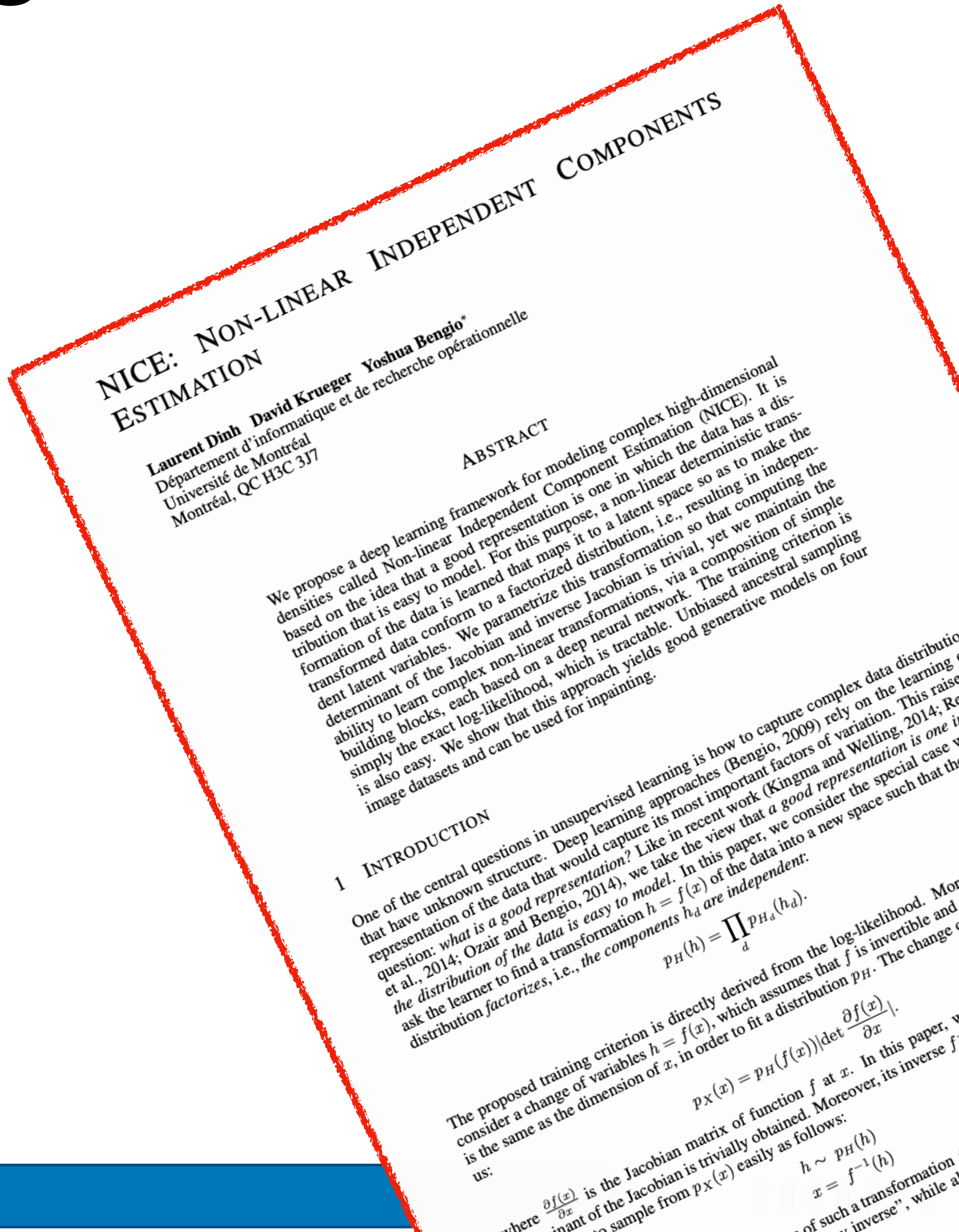
1 INTRODUCTION

How to ensure lower-triangular Jacobian matrix?

Coupling layer



$z \in \mathbb{R}^D$



NICE: Non-linear Independent Components Estimation

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Montréal, QC H3C 3J7

Abstract

We propose a deep learning framework for modeling complex high-dimensional densities called Non-linear Independent Component Estimation (NICE). It is based on the idea that a good representation is one in which the data has a distribution that is easy to model. For this purpose, a non-linear deterministic transformation of the data is learned that maps it to a latent space so as to make the transformed data conform to a factorized distribution, i.e., resulting in independent latent variables. We parametrize this transformation so that computing the determinant of the Jacobian and inverse Jacobian is trivial, yet we maintain the ability to learn complex non-linear transformations, via a composition of simple building blocks, each based on a deep neural network. The training criterion is simply the exact log-likelihood, which is tractable. Unbiased ancestral sampling is also easy. We show that this approach yields good generative models on four image datasets and can be used for inpainting.

1 Introduction

Neural Importance Sampling

Thomas Müller
Brian McWilliams
Fabrice Rousselle
Markus Gross
Jan Novák

Affiliation: NVIDIA

Work done while at: ETH zürich, Disney Research, cgl computer graphics laboratory


Render time: sometimes >100 cpu-hours


512 paths per pixel
Path tracing
Neural path guiding

Path tracing: BSDF sampling

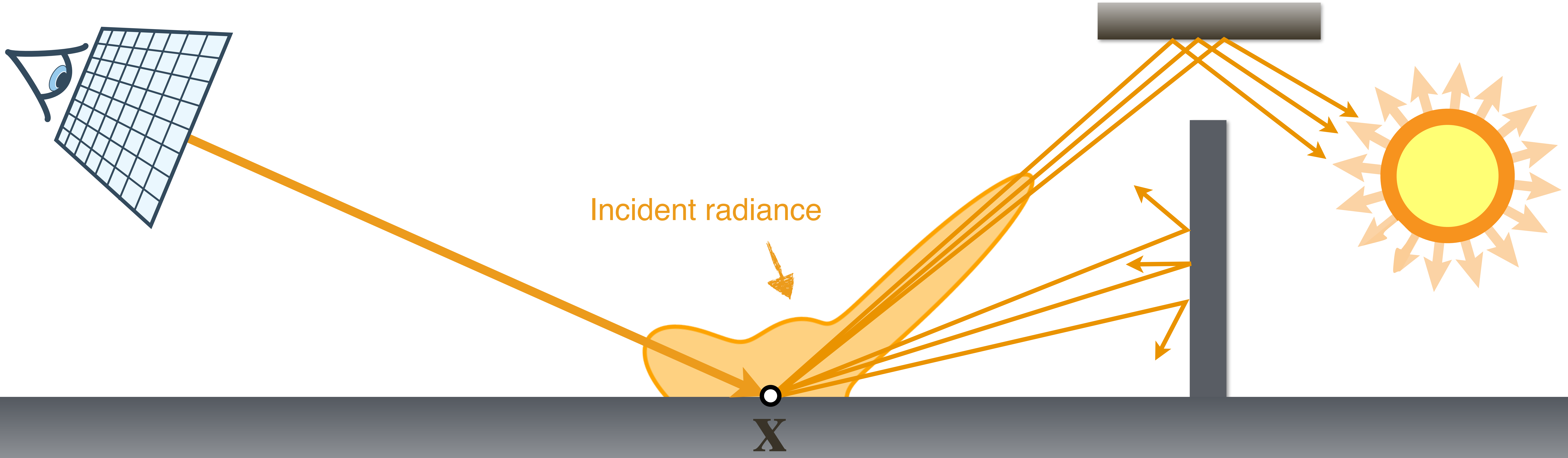
Path tracing: direct-illumination sampling

Multiple Importance Sampling
[Veach and Guibas 1995]

Where is path guiding useful?

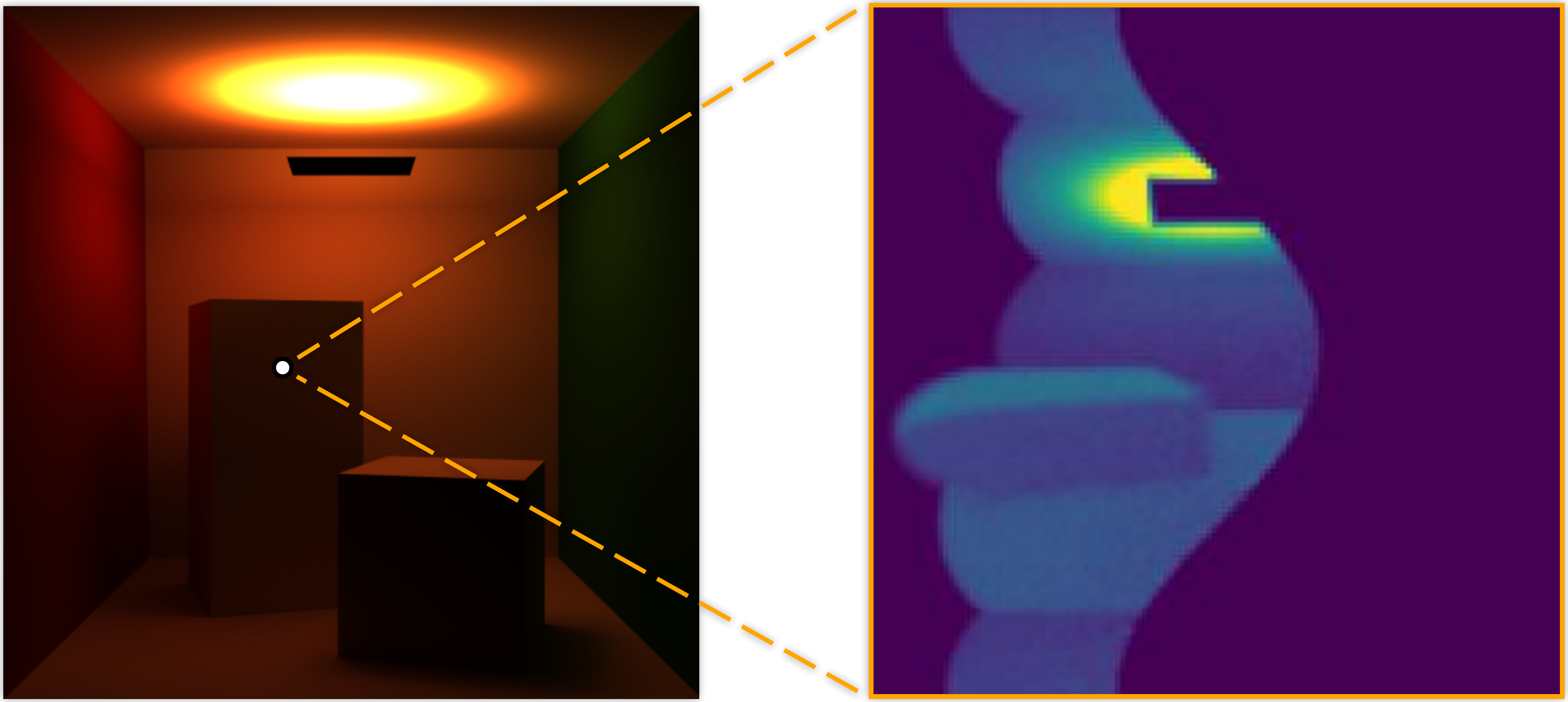
Where is path guiding useful?

Goal: Sample proportional to incident radiance.



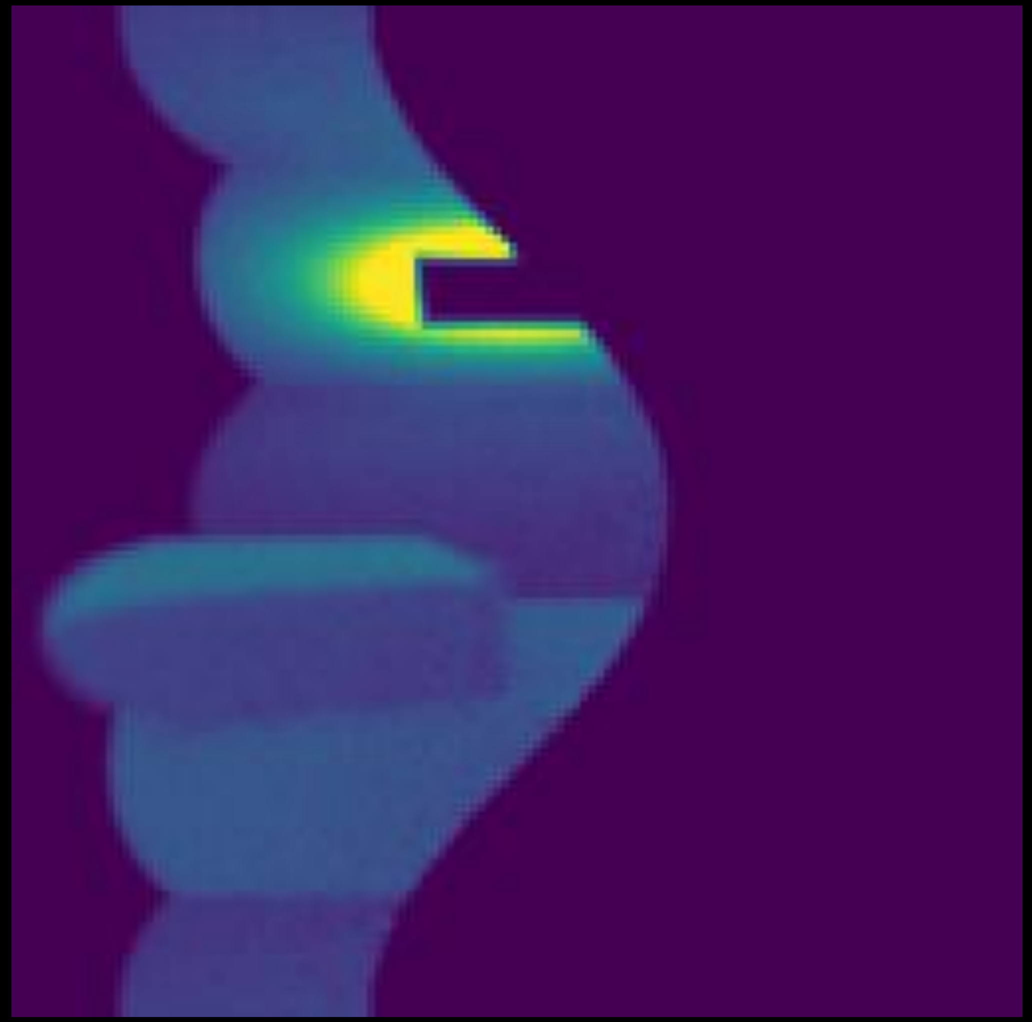
Where is path guiding useful?

Learning incident radiance in a Cornell box

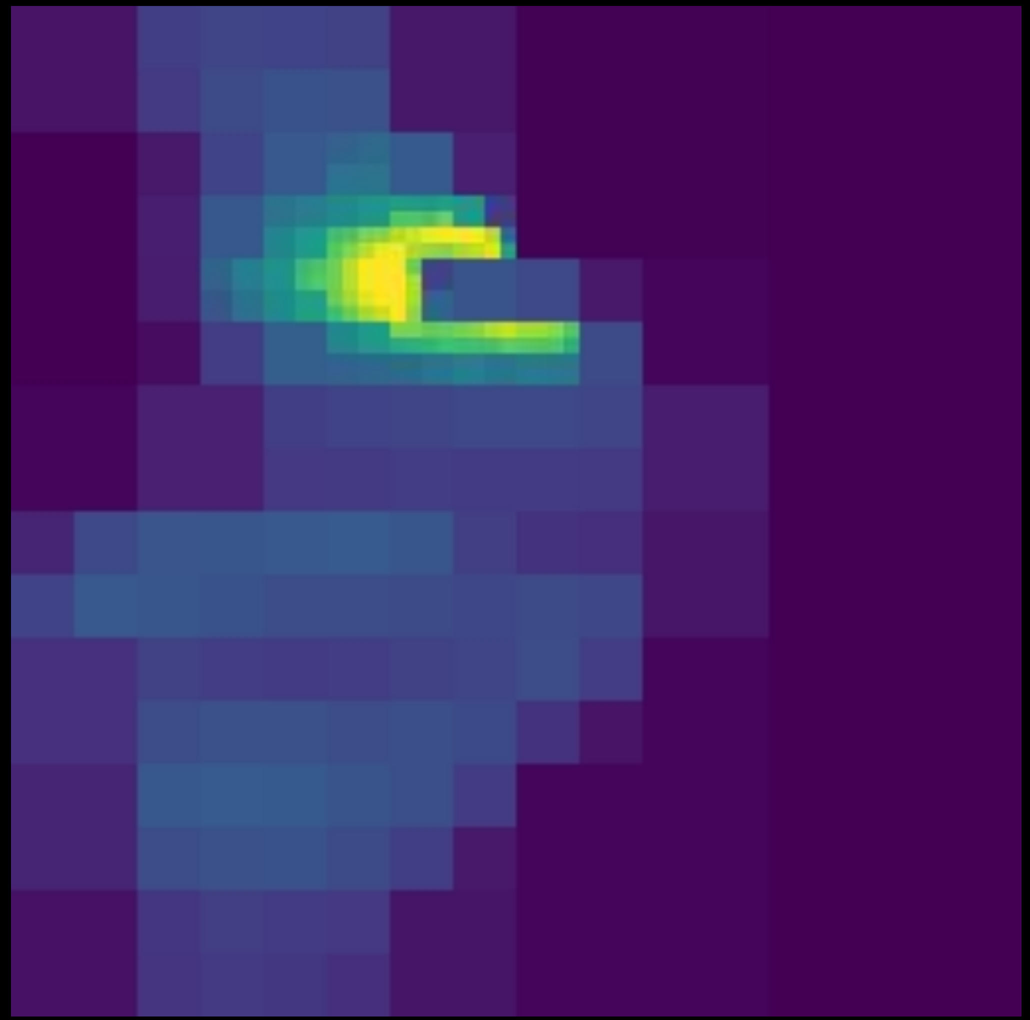


Neural networks as function approximators

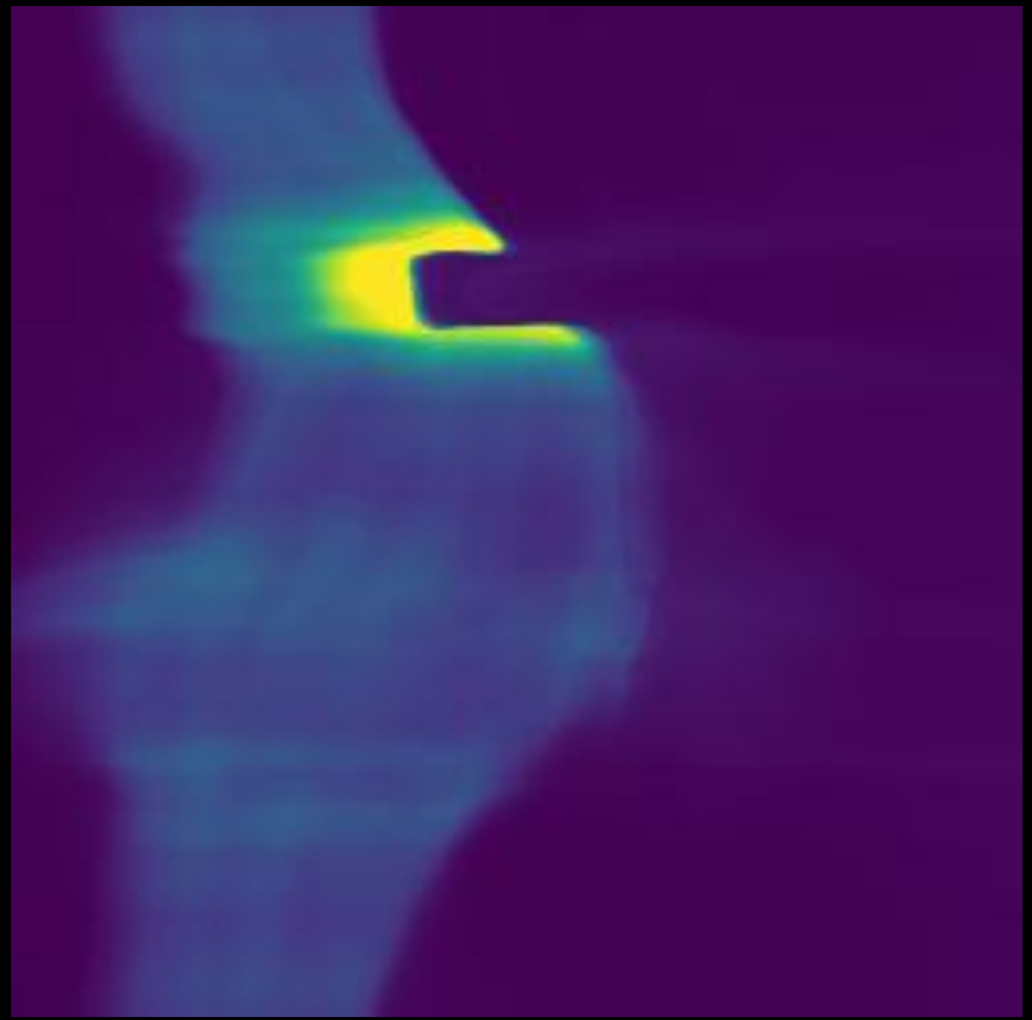
Reference



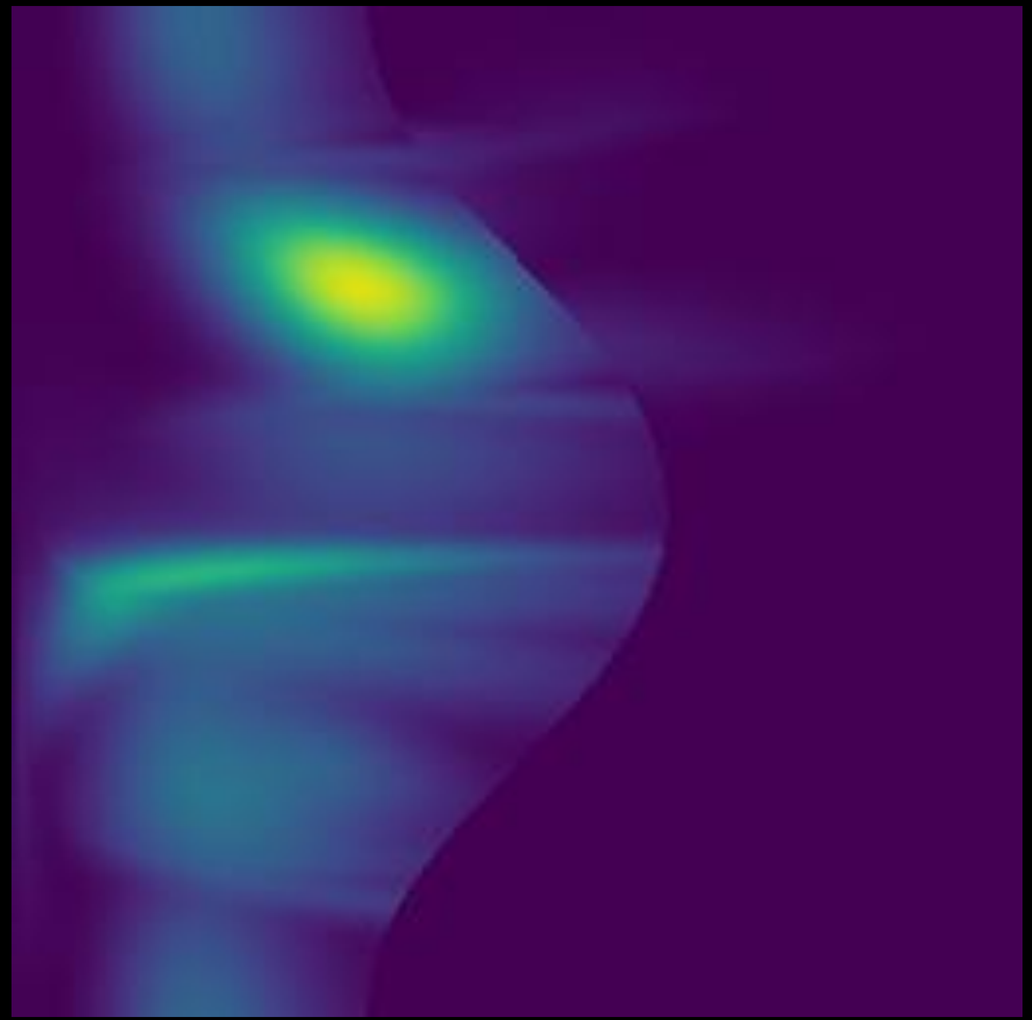
SD-tree [Müller et al. 2017]

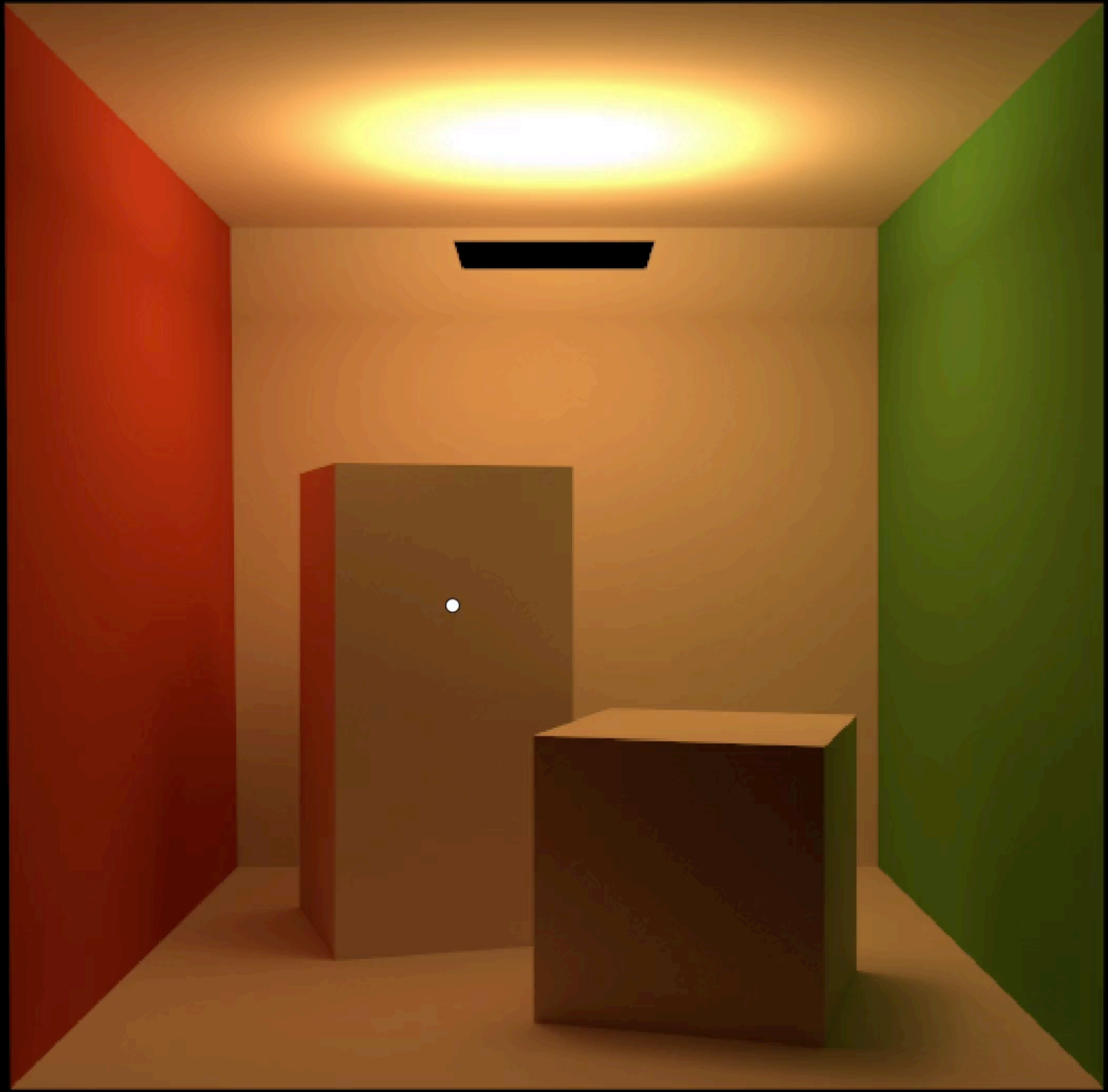


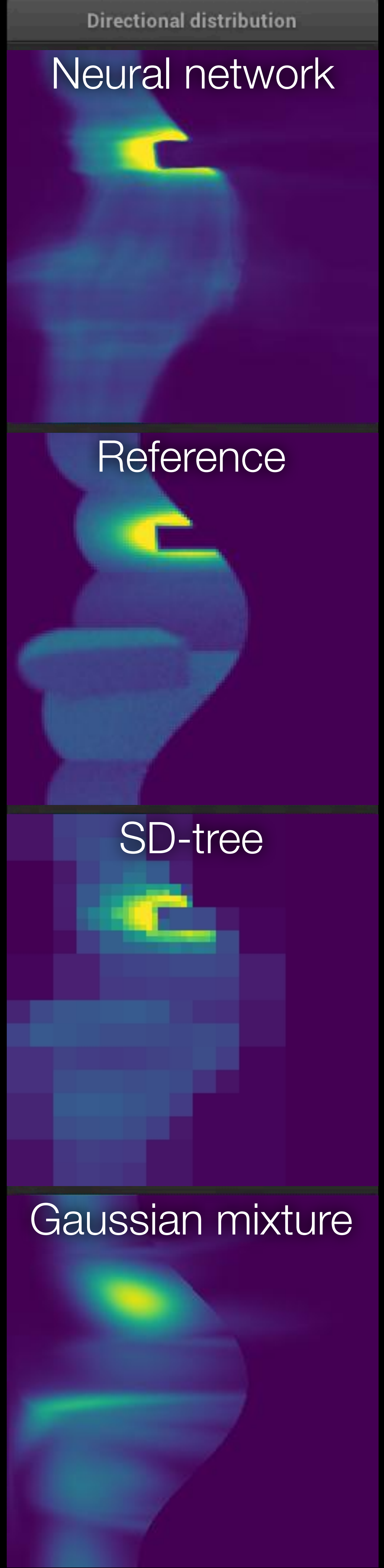
Neural Network



GMM [Vorba et al. 2014]



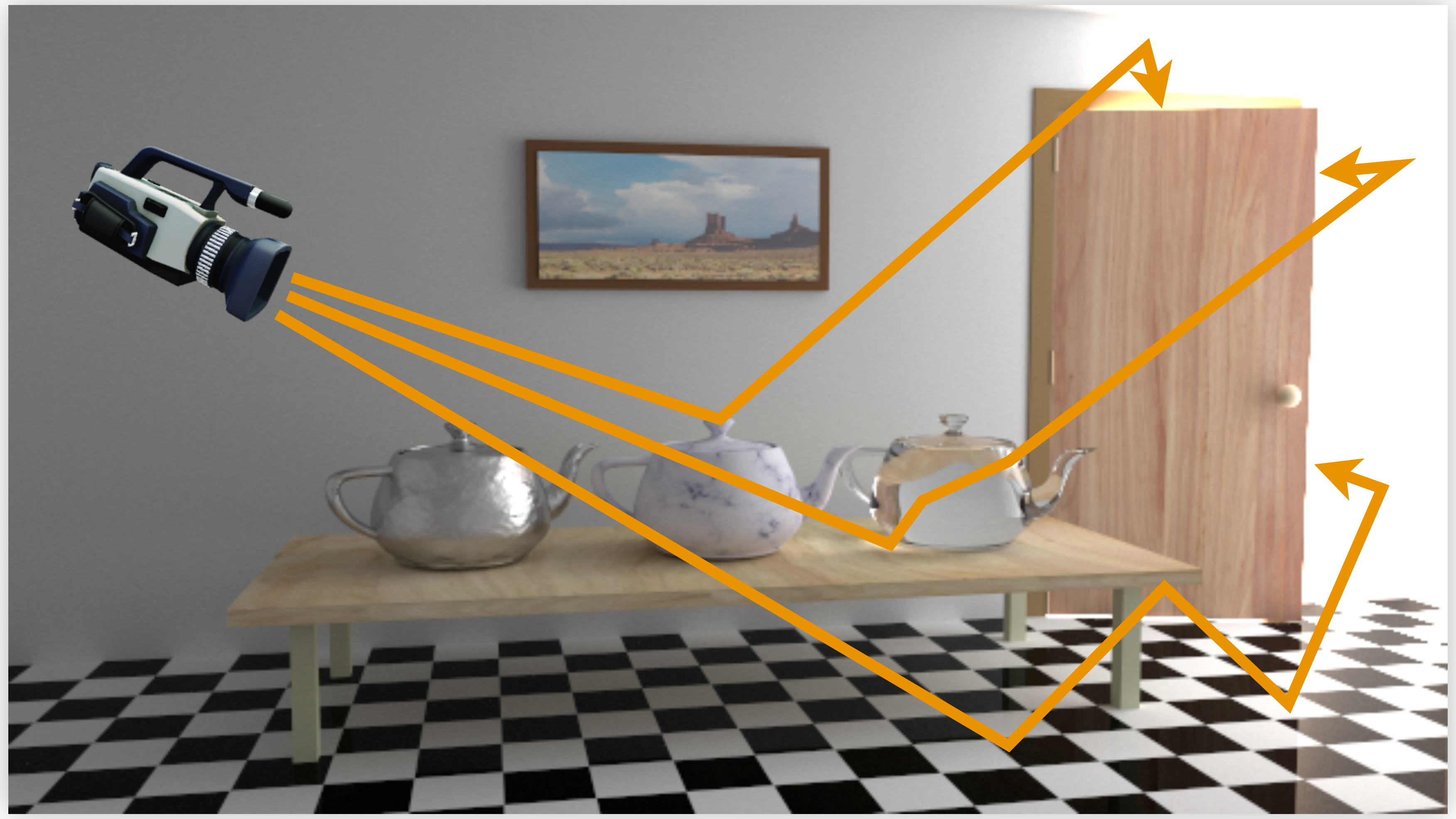




Directional distribution
Neural network
Reference
SD-tree
Gaussian mixture

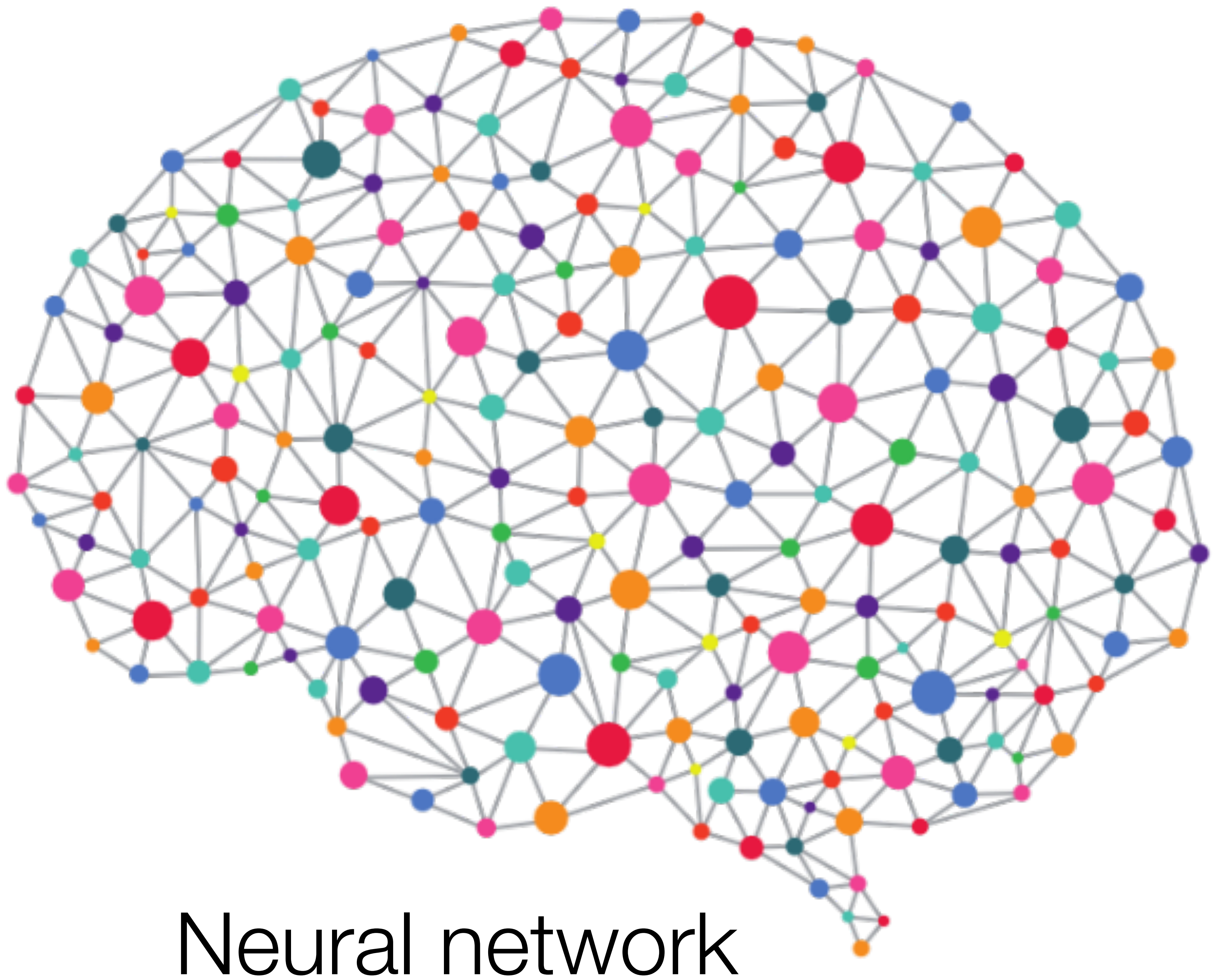
Neural path guiding overview

Sample



Path tracer

Feedback loop



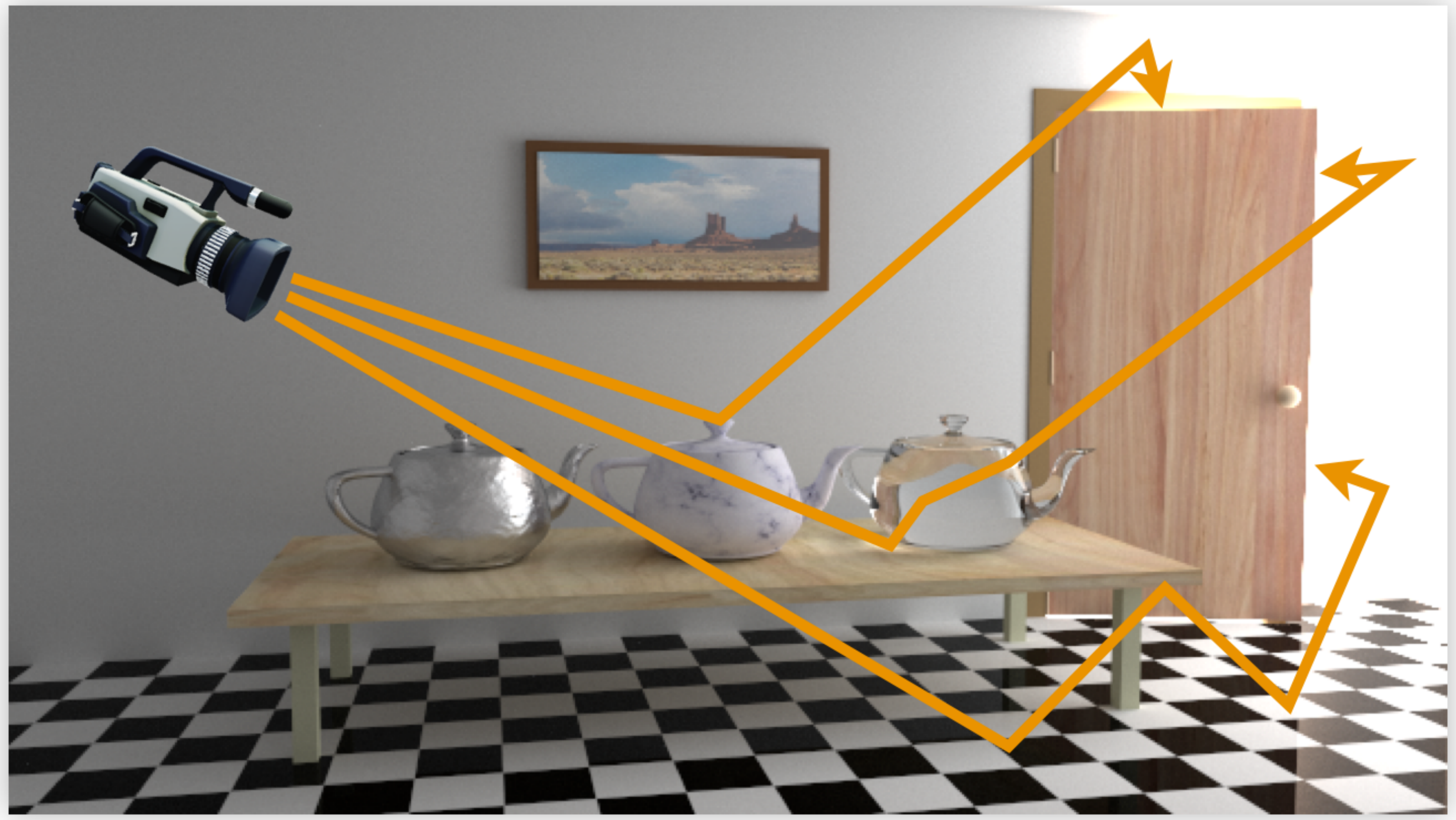
Neural network

Optimize

Neural path guiding overview

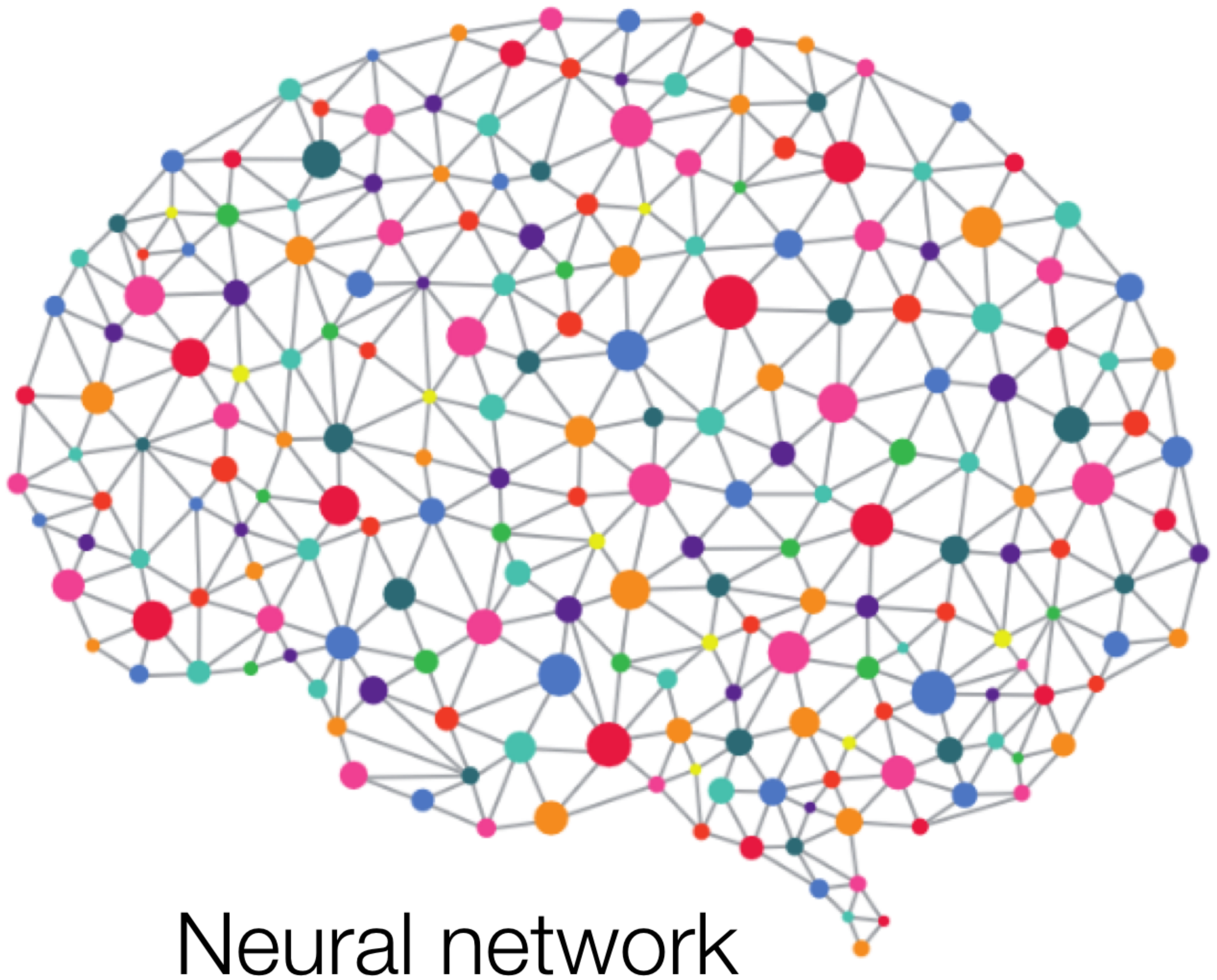
How?

Sample



Path tracer

Feedback loop



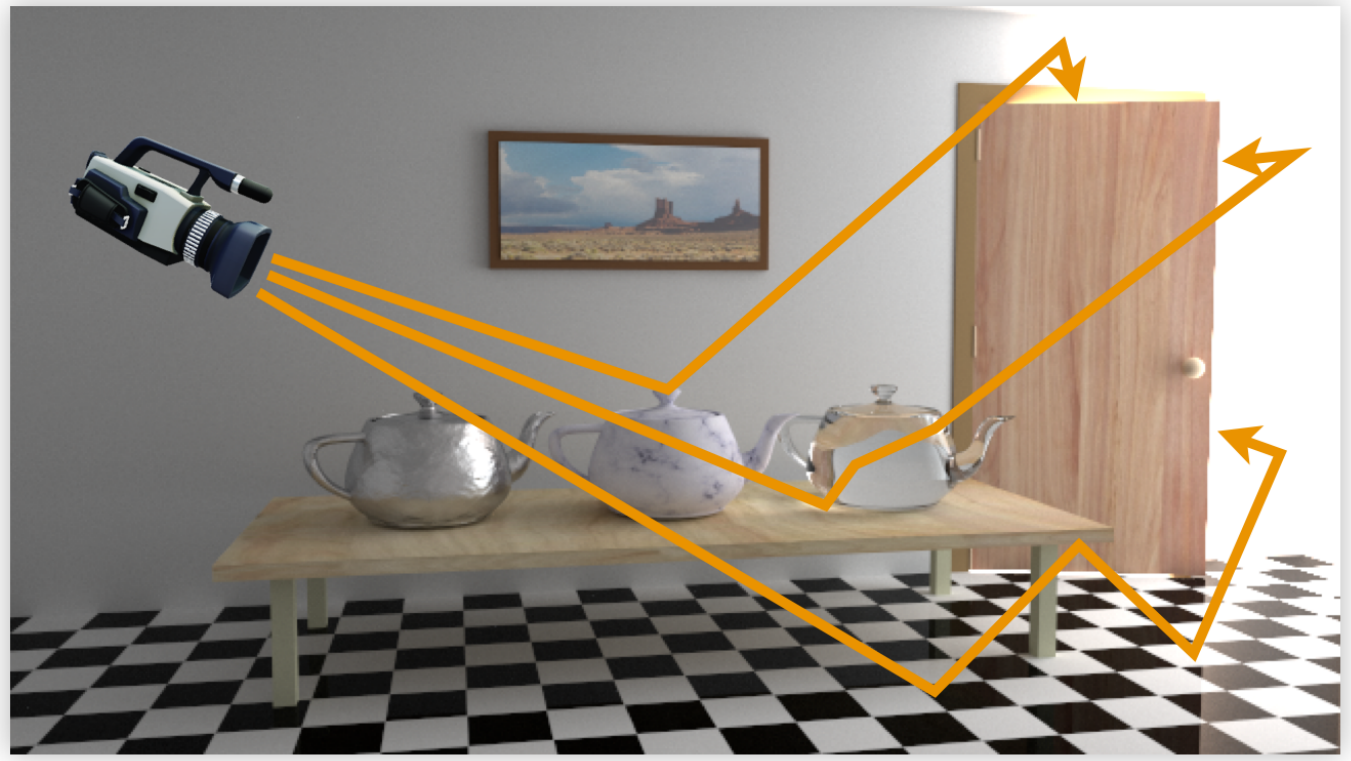
Neural network

Optimize

How?

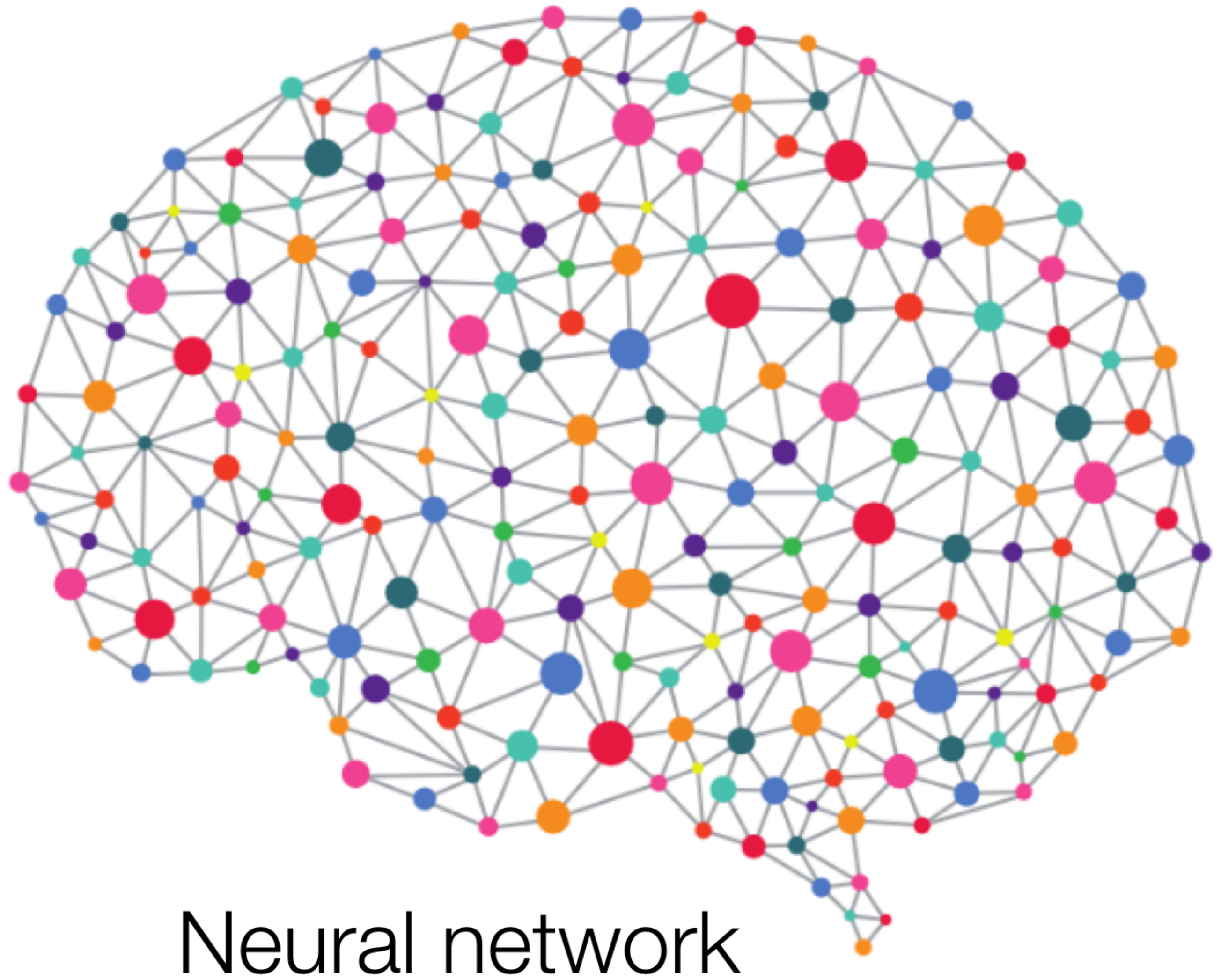
How to draw samples?

Sample



Path tracer

Feedback loop



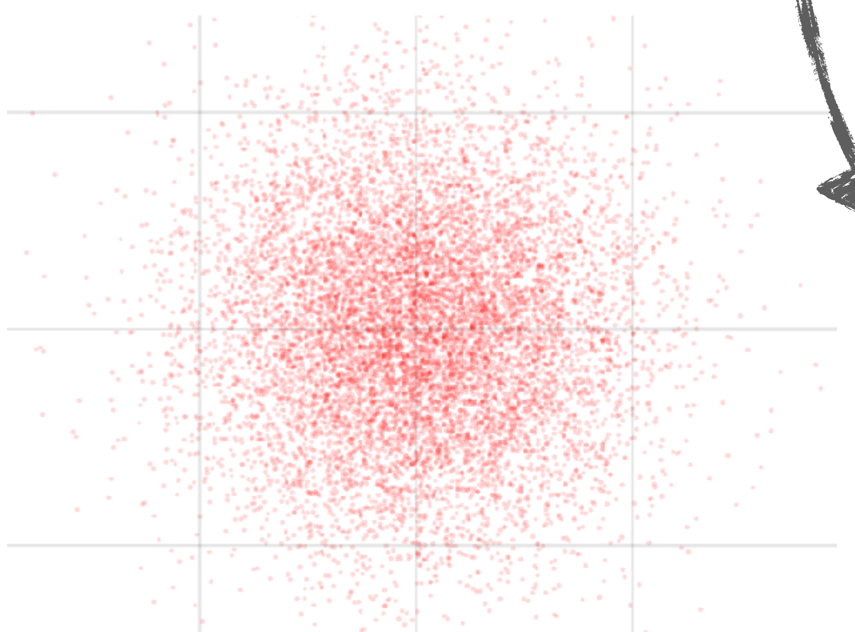
Neural network

Optimize

Goal: warp random numbers to good distribution with NN

Random number

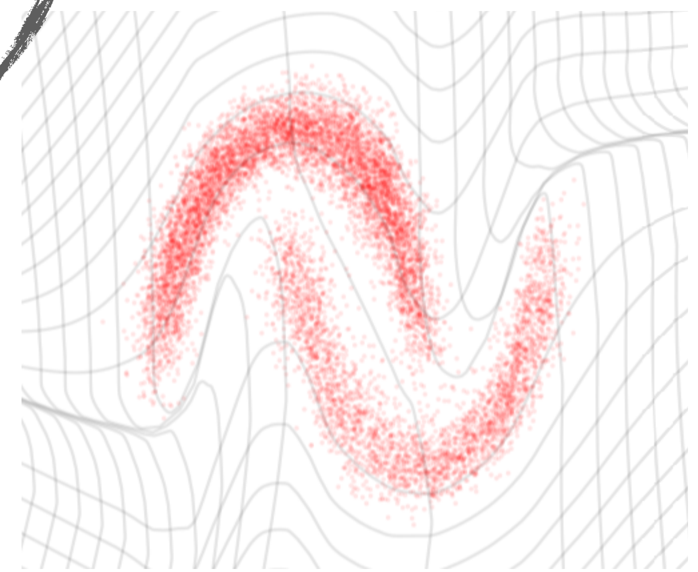
Sample



[Dinh et al. 2016]

$z \rightarrow$

$\rightarrow x$



[Dinh et al. 2016]

Monte Carlo estimator

$$F \approx \frac{1}{N} \sum_{i=1}^{N} \frac{f(X_i)}{p(X_i)}$$

Need p in closed form!

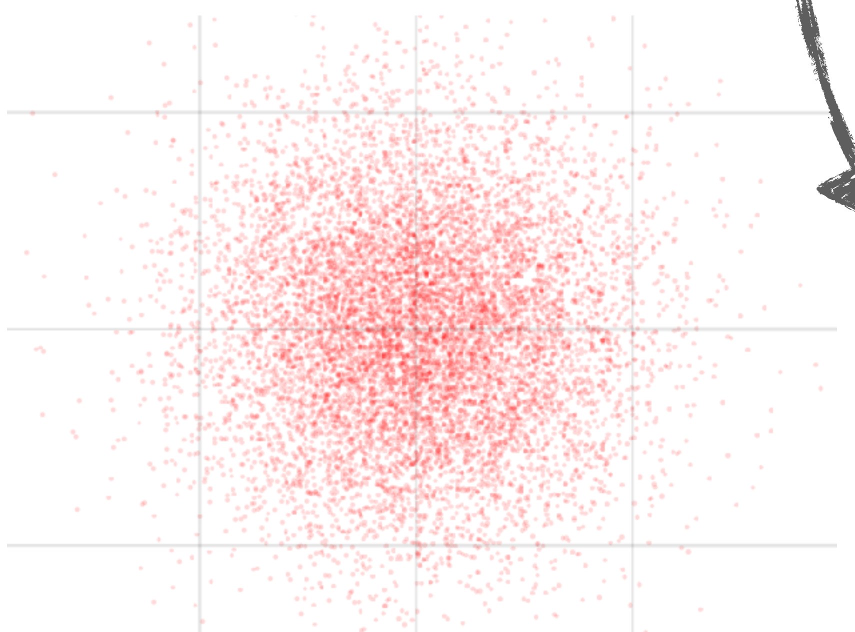
Addressed by "normalizing flows"

Parameterizing a bijection allows using the change-of-variable formula

Random number

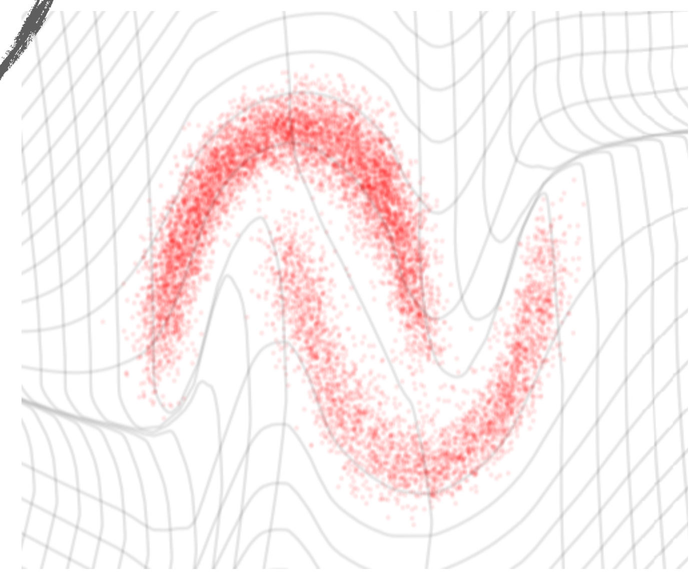
Parametric bijective function

Sample



[Dinh et al. 2016]

$$z \longrightarrow m(z;\phi) \longrightarrow x$$



[Dinh et al. 2016]

$$p(x) = p(z) \cdot \left| det\left(\frac{\partial m(z)}{\partial z^T}\right)\right|^{-1}$$

Our choice, e.g. Gaussian

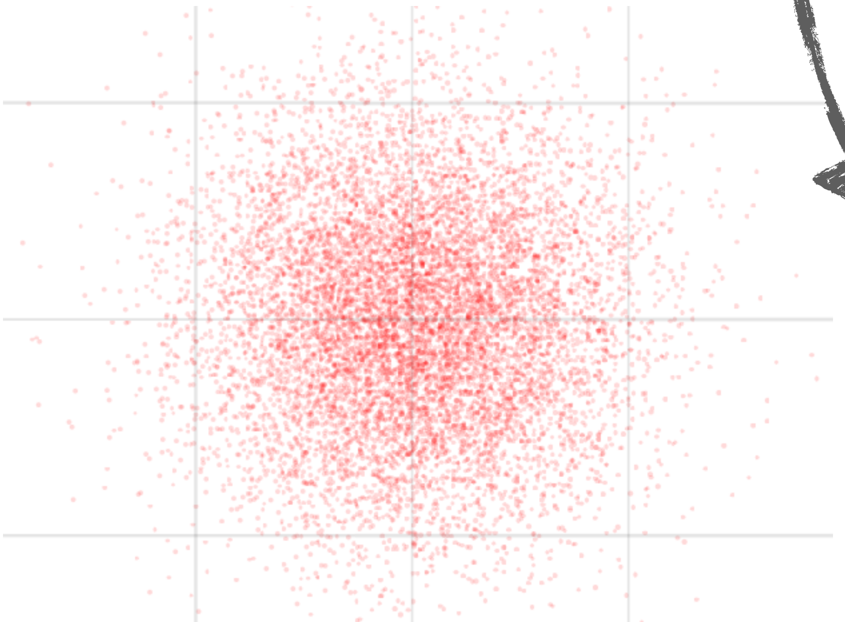
Squishing/stretching by m

A chain of simple bijections can model complicated functions

Random number

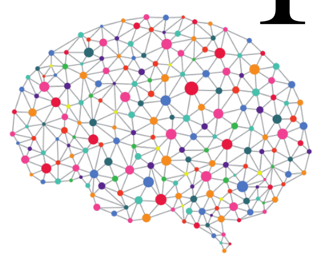
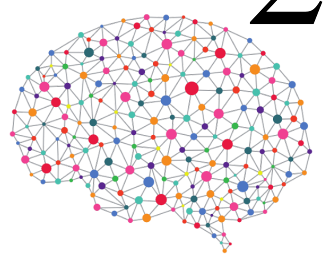
Parametric bijective functions
(normalizing flow)

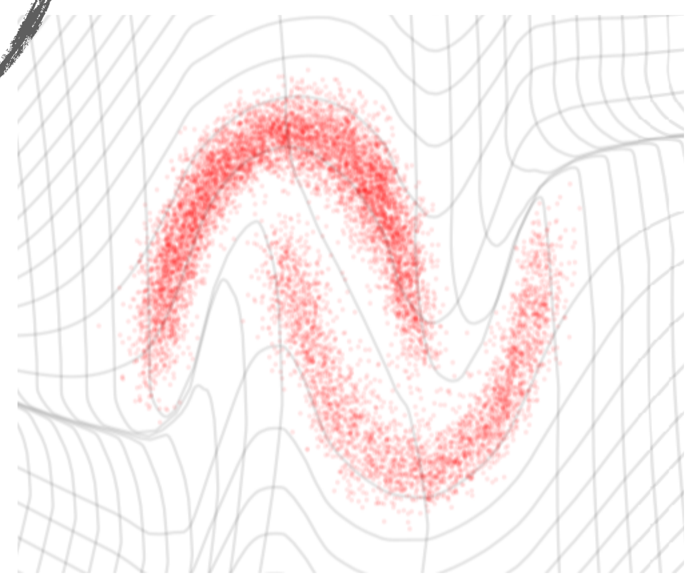
Sample



[Dinh et al. 2016]

$$z \longrightarrow m_1 \circ m_2 \circ \ldots \circ m_L \longrightarrow x$$

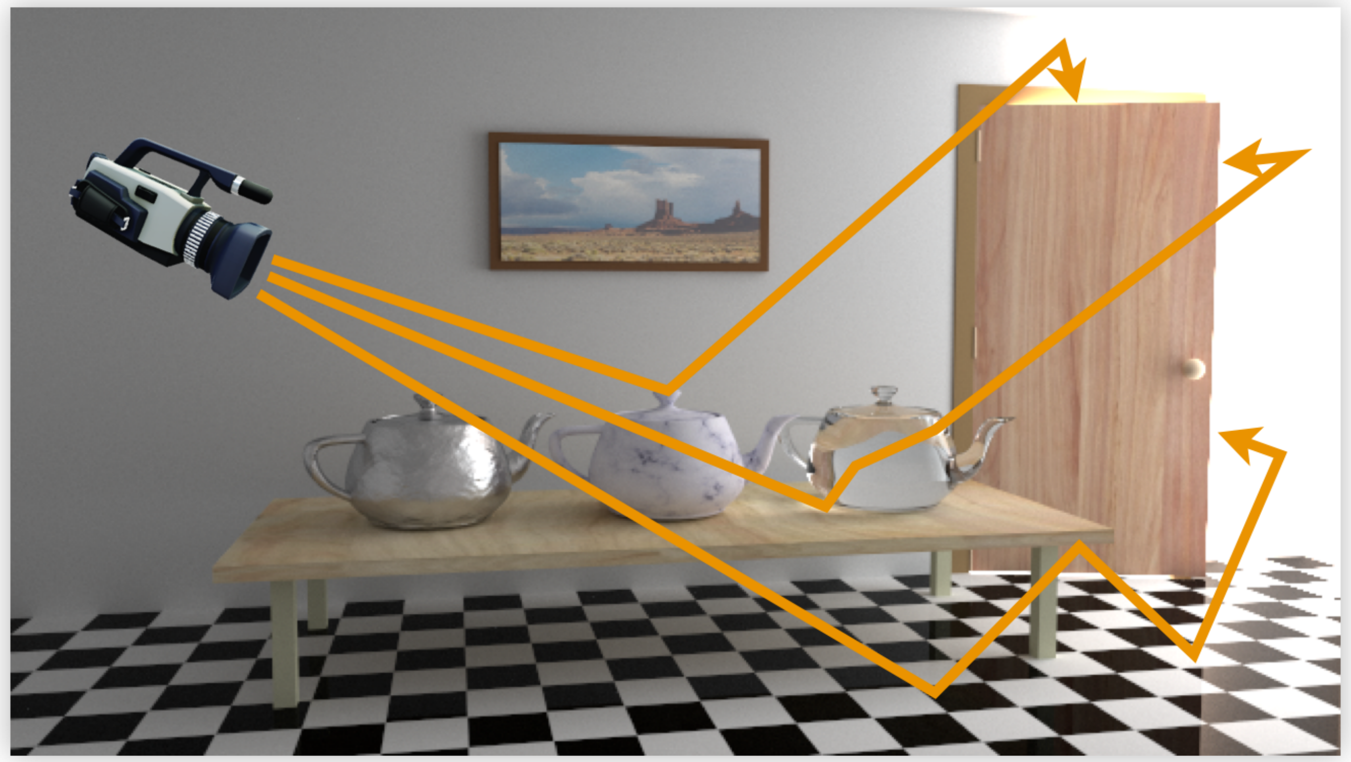
[Dinh et al. 2016]

$$p(x) = p(z) \cdot \prod_{i=1}^{L} \left| det\left(\frac{\partial m_i(z)}{\partial z^T}\right) \right|^{-1}$$

Our choice, e.g. Gaussian

Squishing/stretching by m

How to optimize?

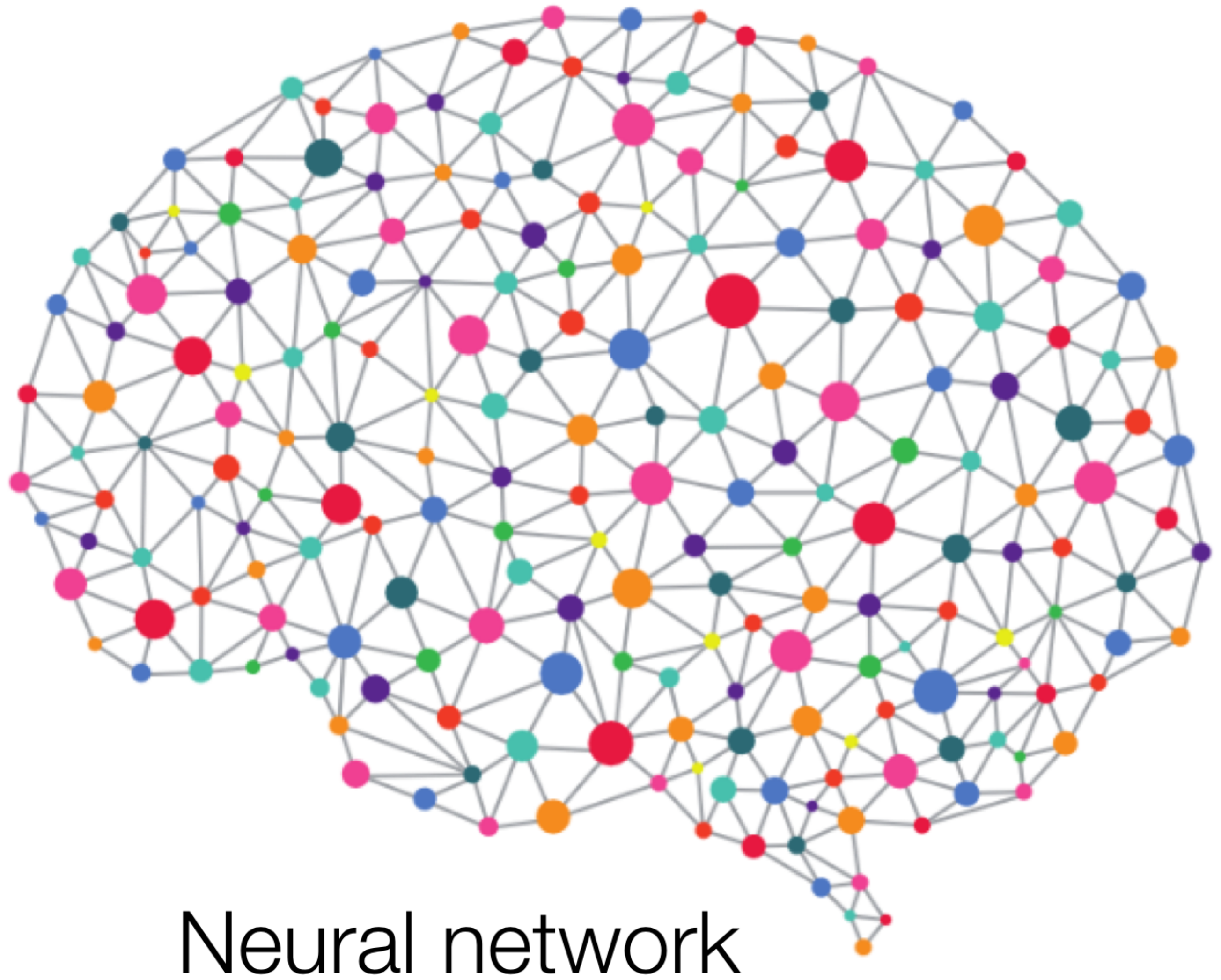


Path tracer

Sample

Feedback loop

Optimize



Neural network

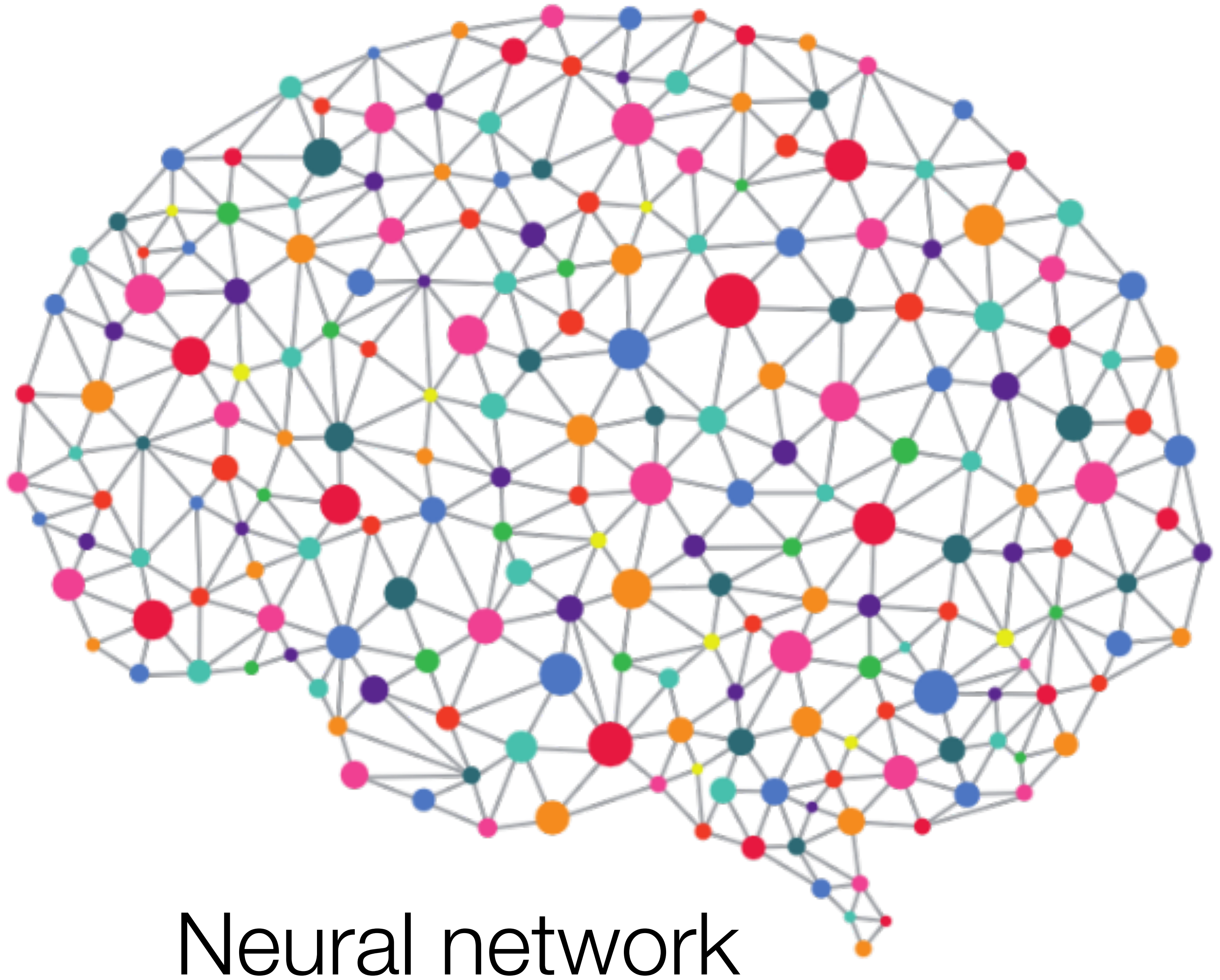
Training with data from the correct distribution is simple

Desired distribution

Training data

Optimize

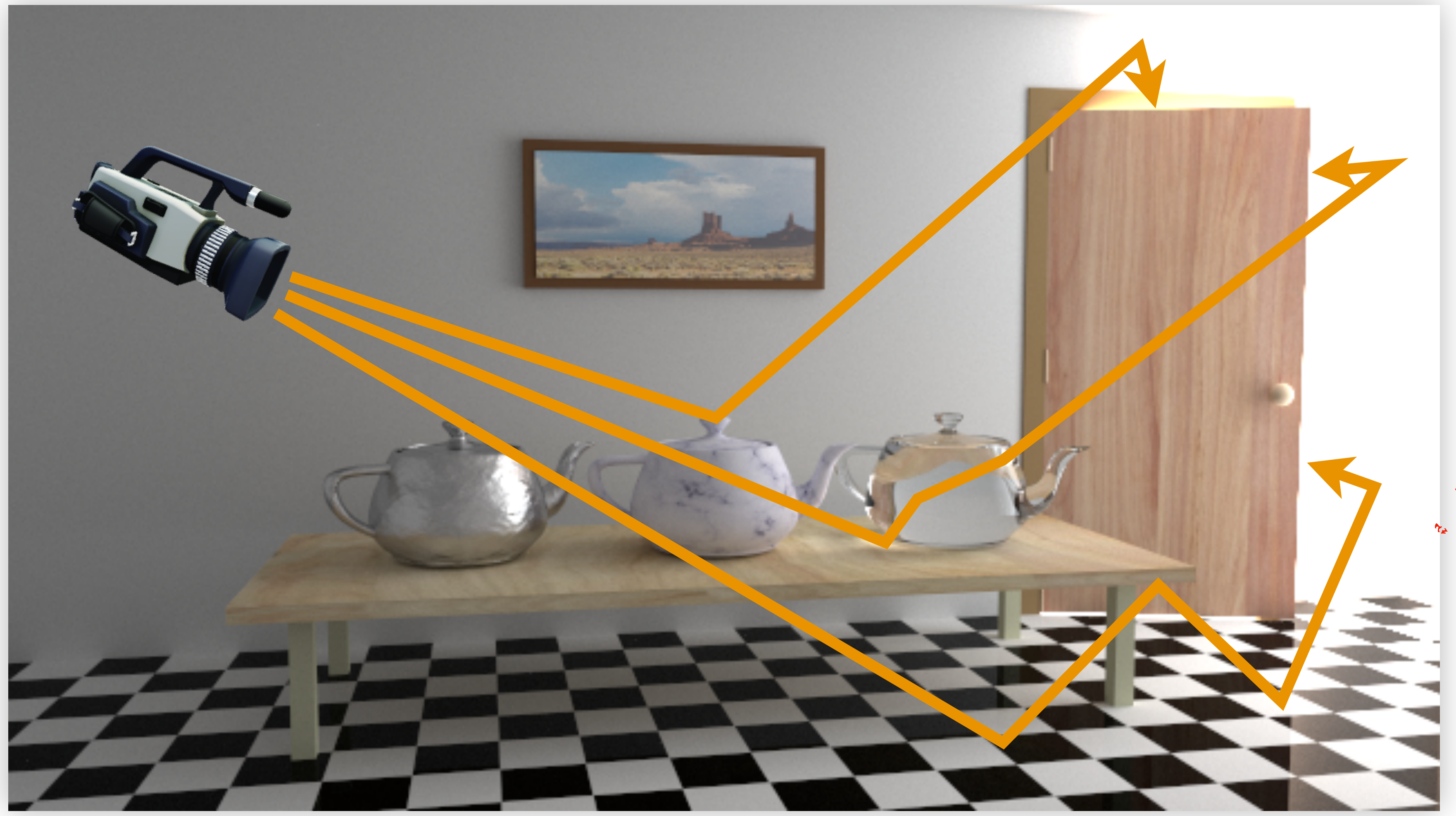
$$\nabla_\theta \log p(x;\theta)$$



Neural network

Training from Monte Carlo samples requires careful weighting

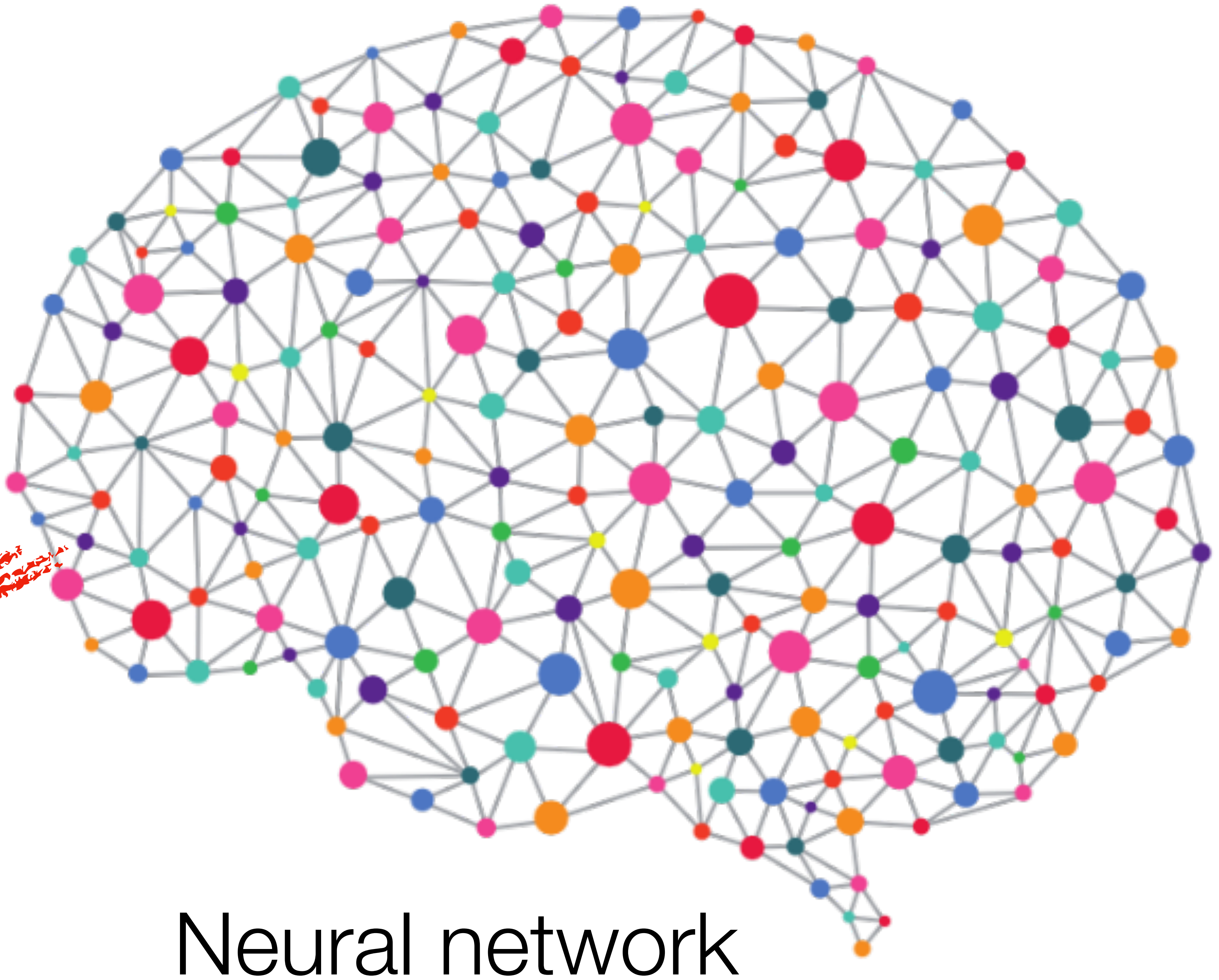
Arbitrarily distributed



Training data

Optimize

$$\nabla_\theta \log p(x;\theta)$$



Neural network

Training with data from the correct distribution is simple

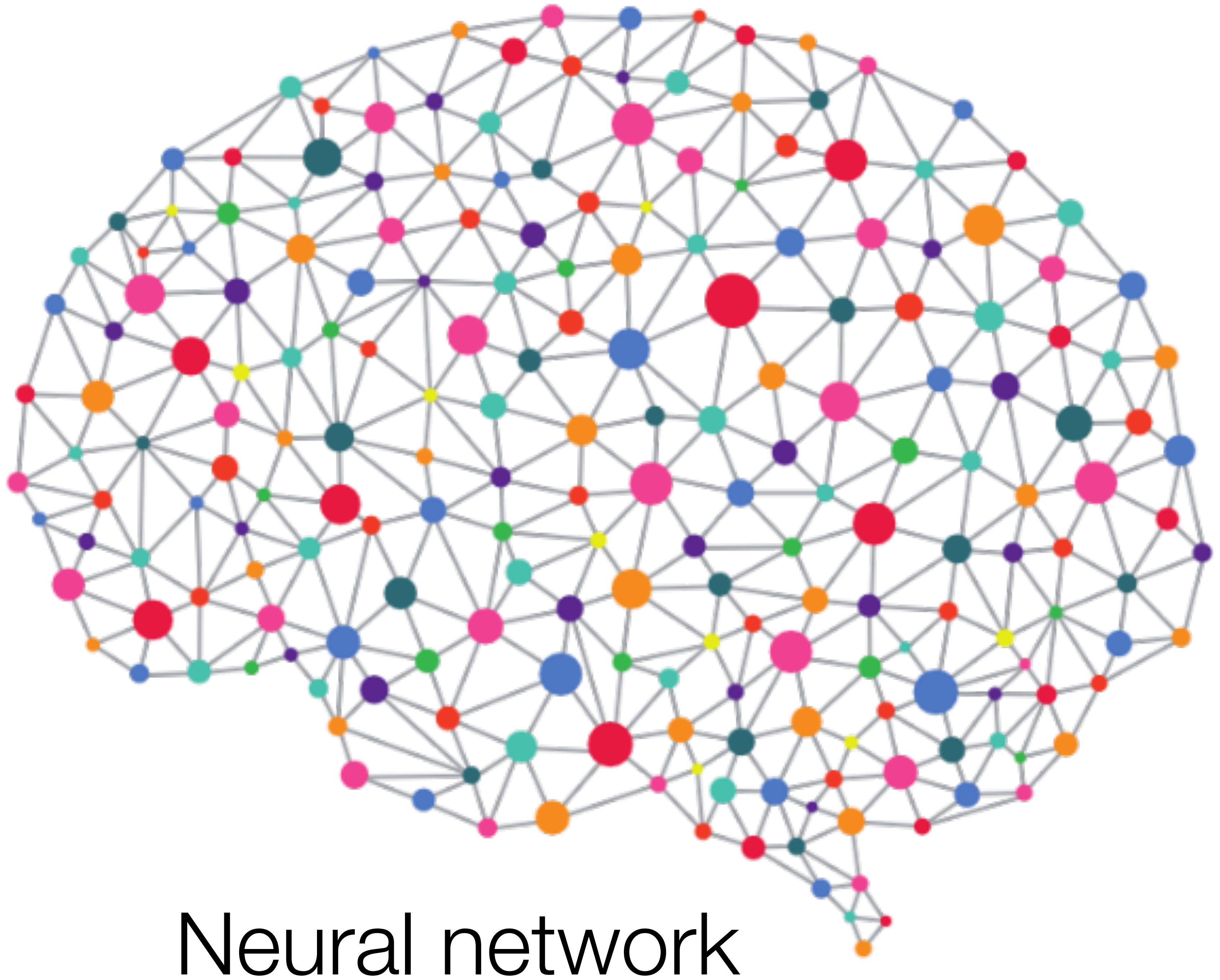
Desired distribution

Training data

Optimize

$$\nabla_\theta \log p(x; \theta)$$

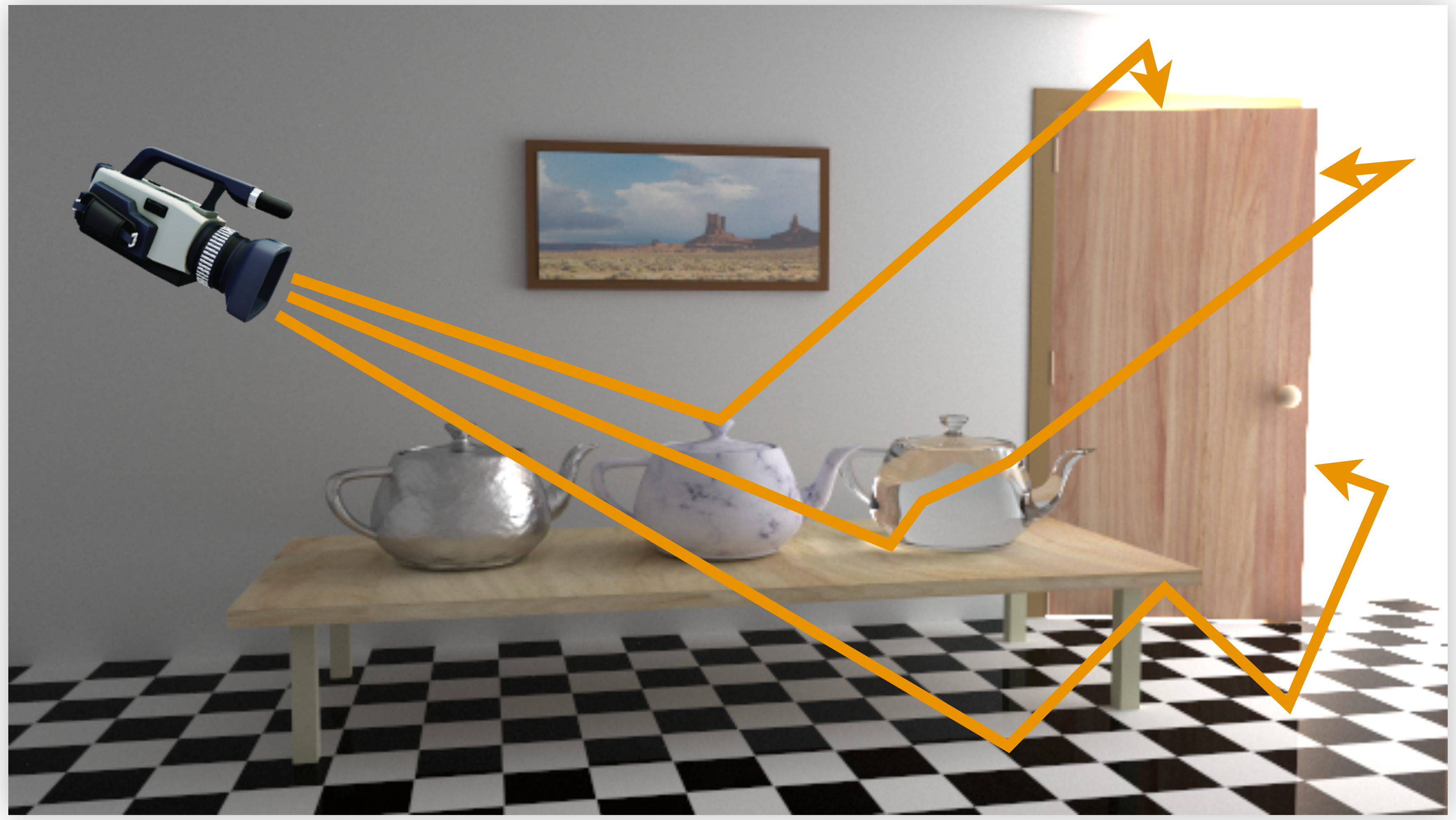
min KL-divergence



Neural network

Training from Monte Carlo samples requires careful weighting

$p(x;\theta)$ distributed

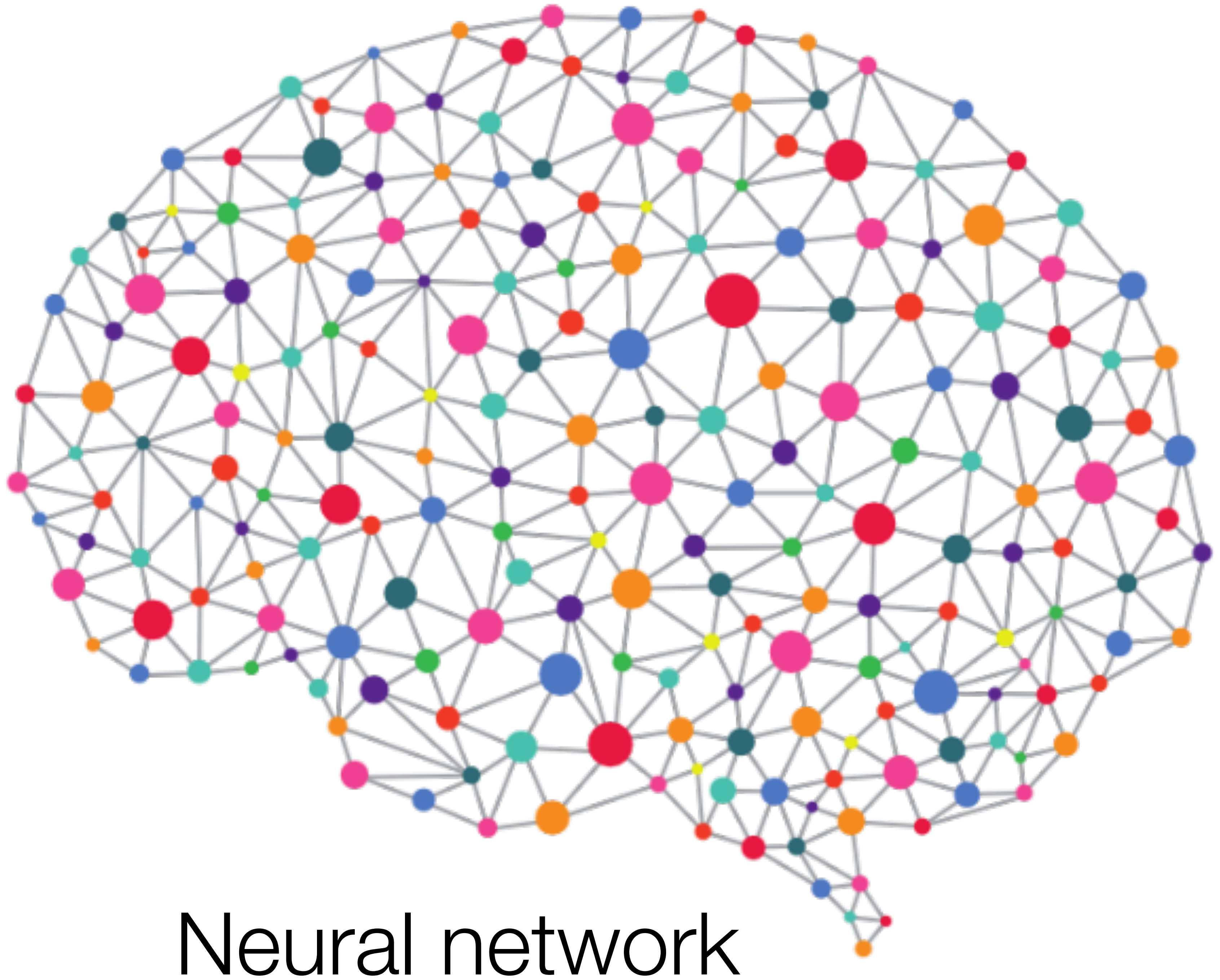


Training data

Optimize

$$\frac{f(x)}{p(x;\theta)} \nabla_\theta \log p(x;\theta)$$

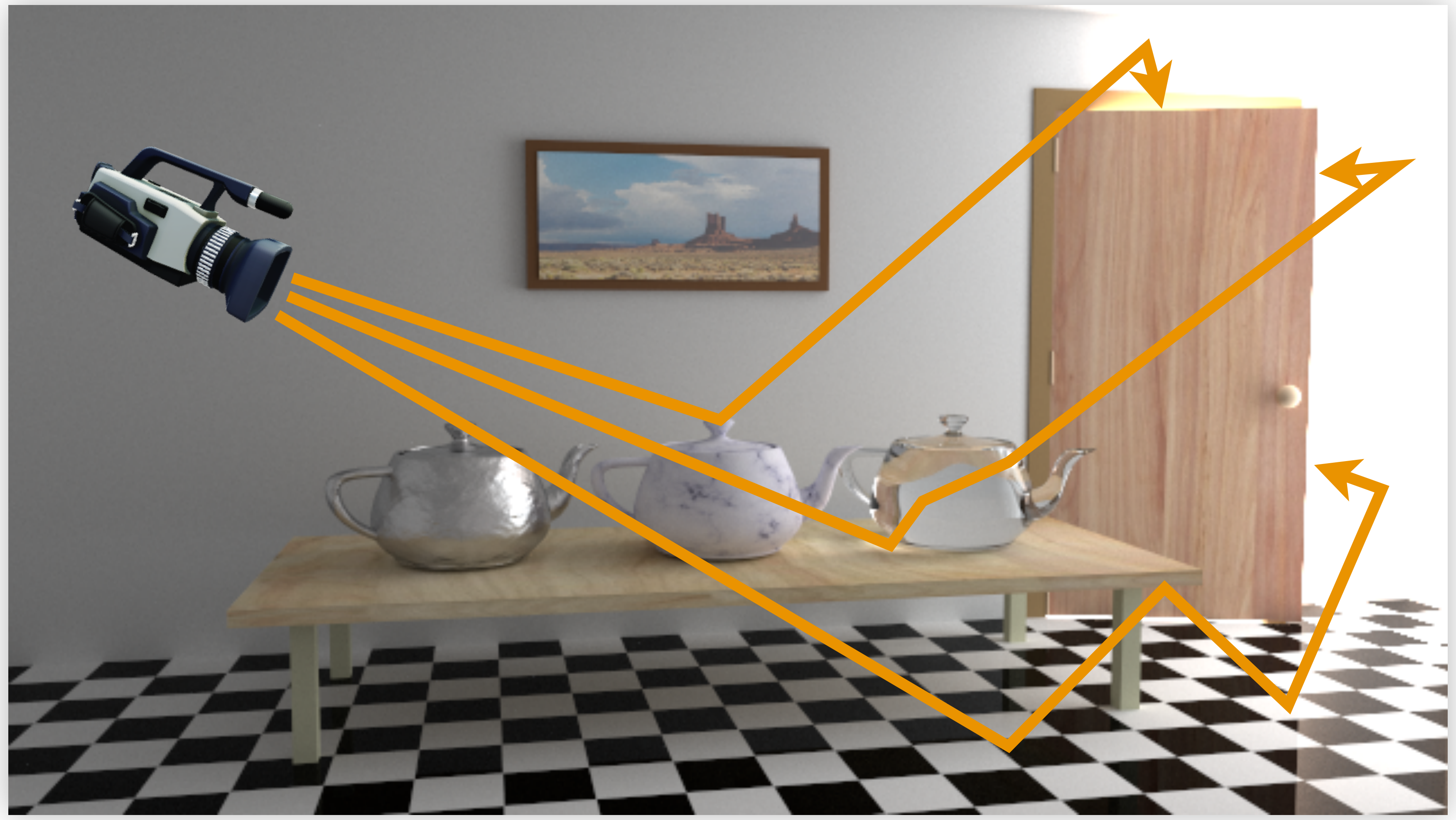
min KL-divergence



Neural network

Training from Monte Carlo samples requires careful weighting

$p(x;\theta)$ distributed

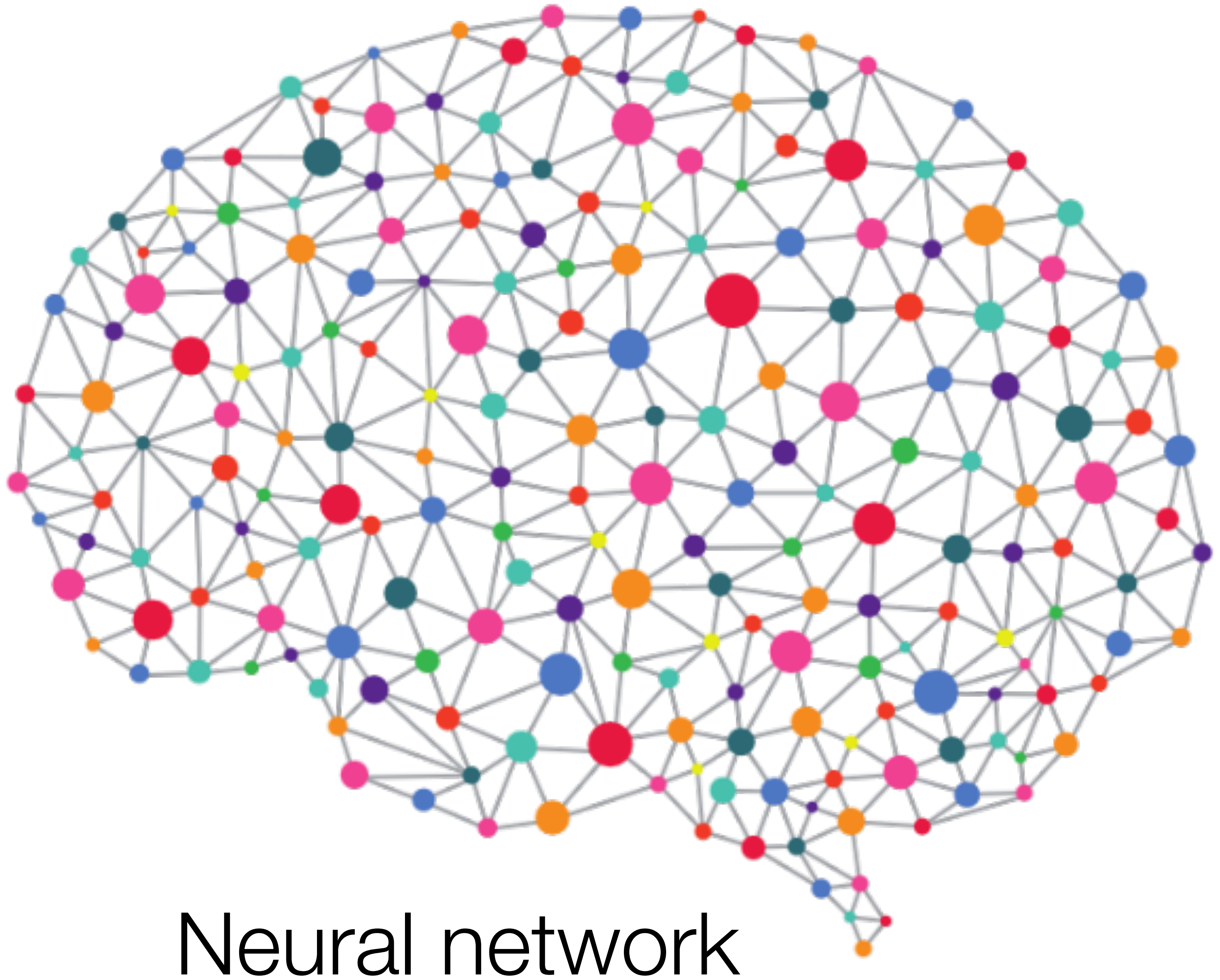


Training data

Optimize

$$\frac{f(x)^2}{p(x;\theta)^2}\nabla_\theta \log p(x;\theta)$$

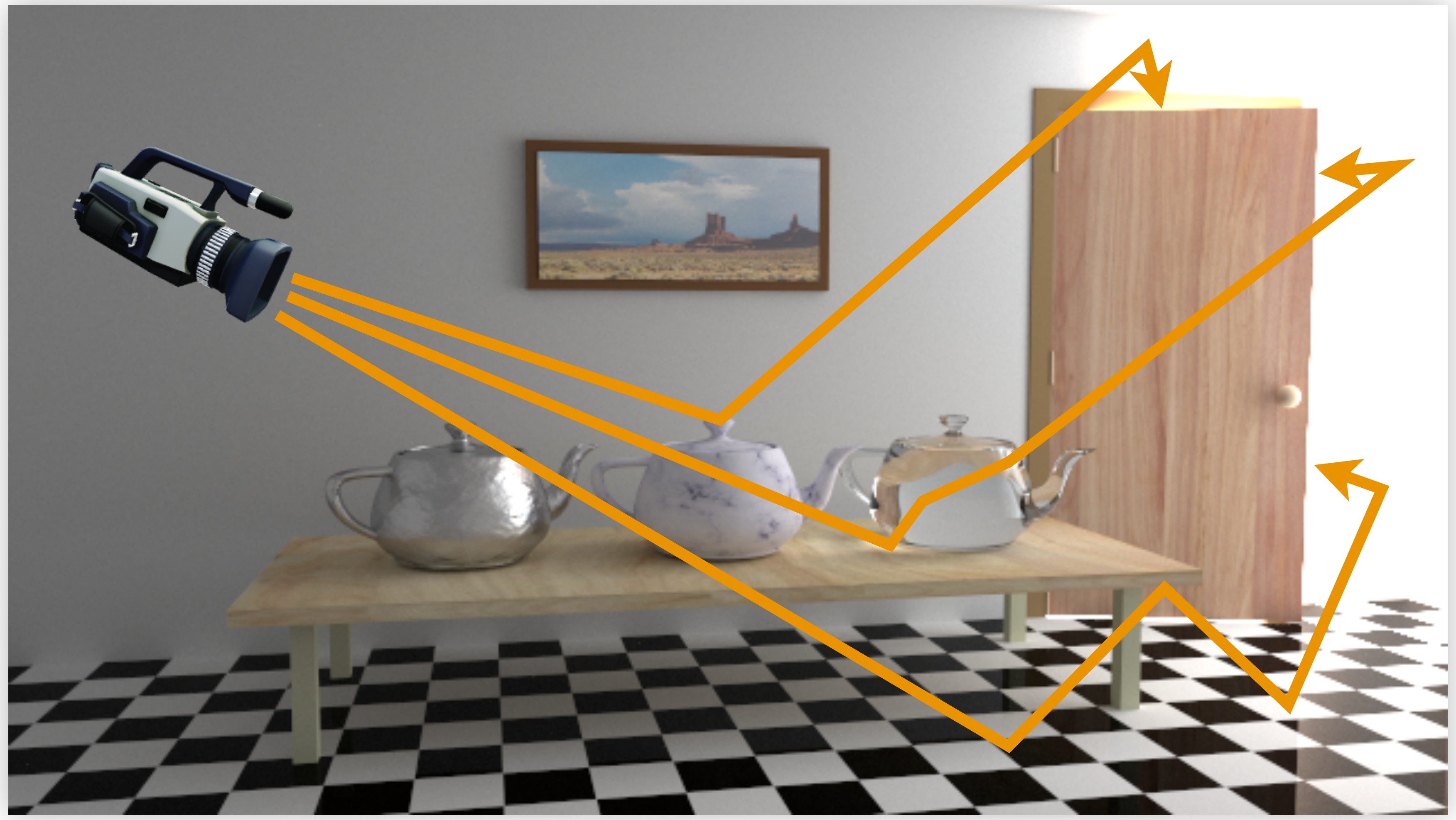
min variance



Neural network

Training from Monte Carlo samples requires careful weighting

$p(x;\theta)$ distributed

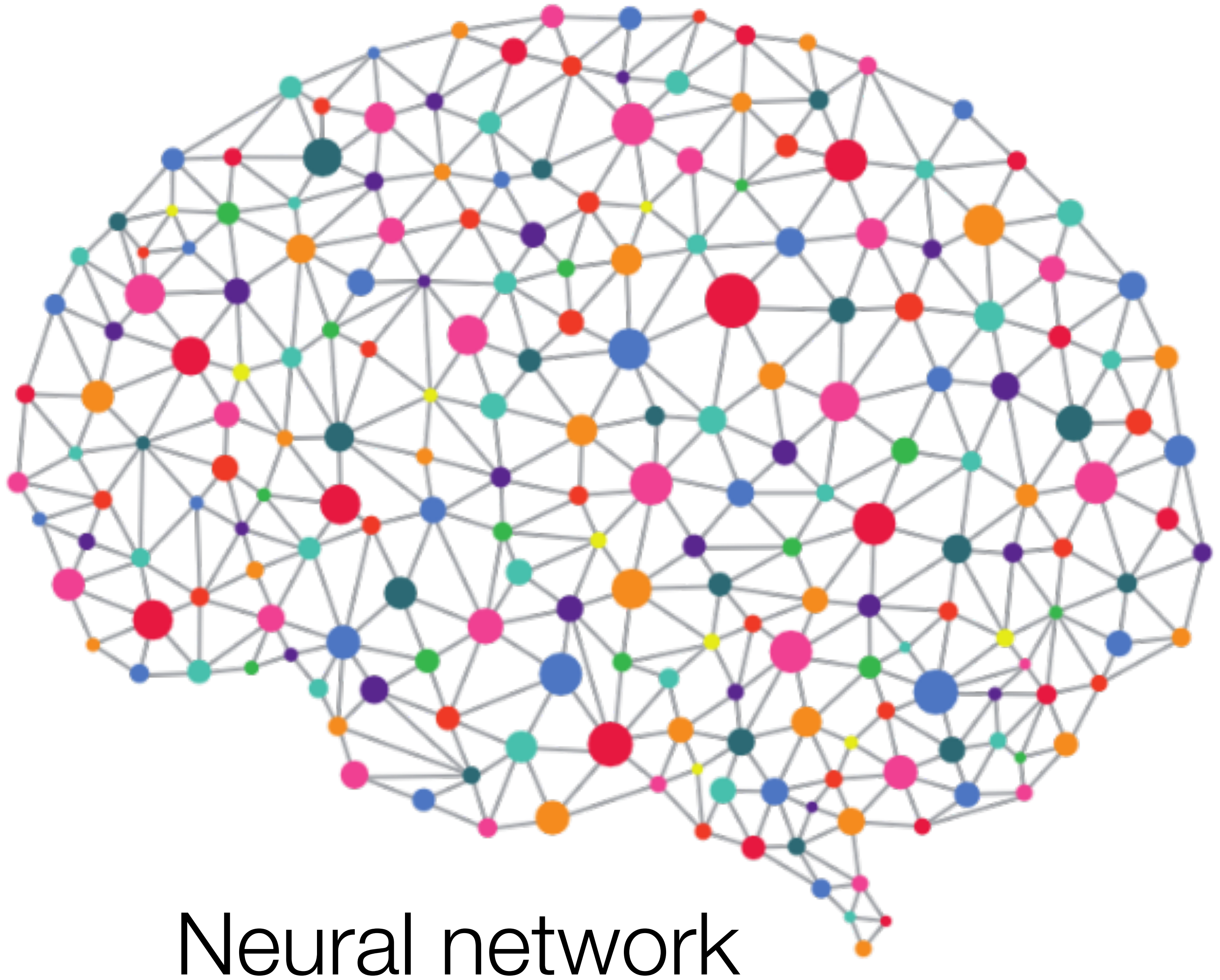


Training data

Optimize

$$\frac{f(x)^2}{p(x;\theta)^2}\nabla_\theta \log p(x;\theta)$$

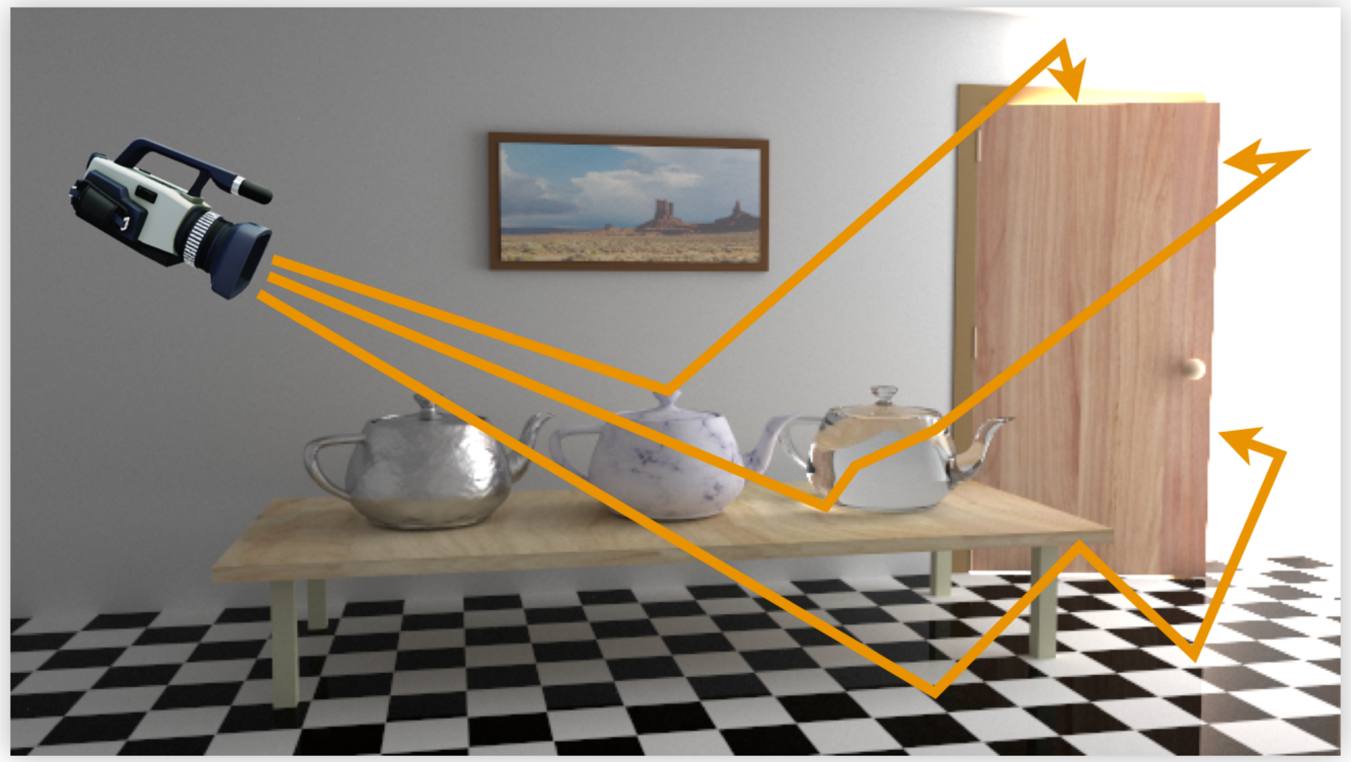
min χ^2-divergence



Neural network

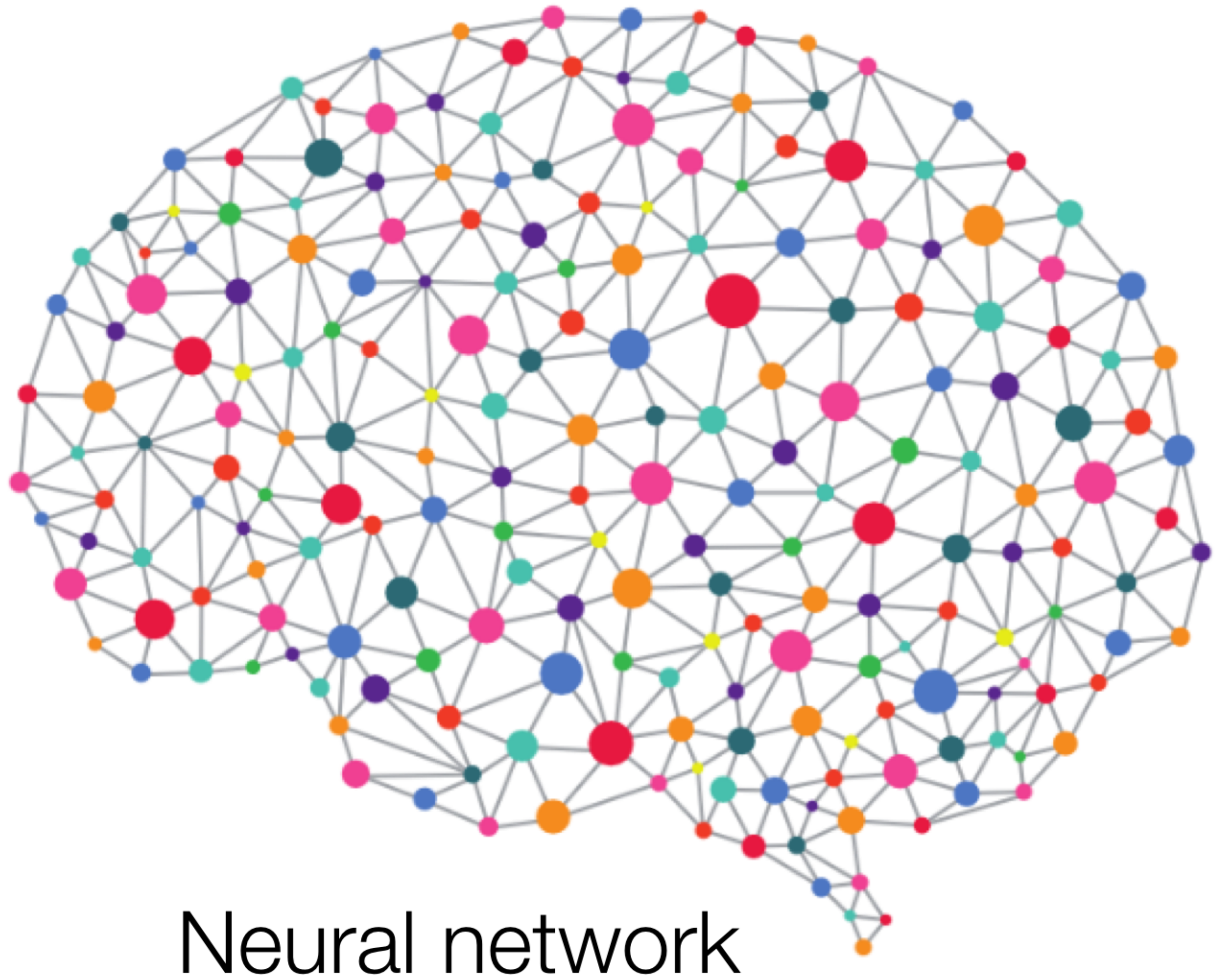
Putting it together...

Sample



Path tracer

Feedback loop

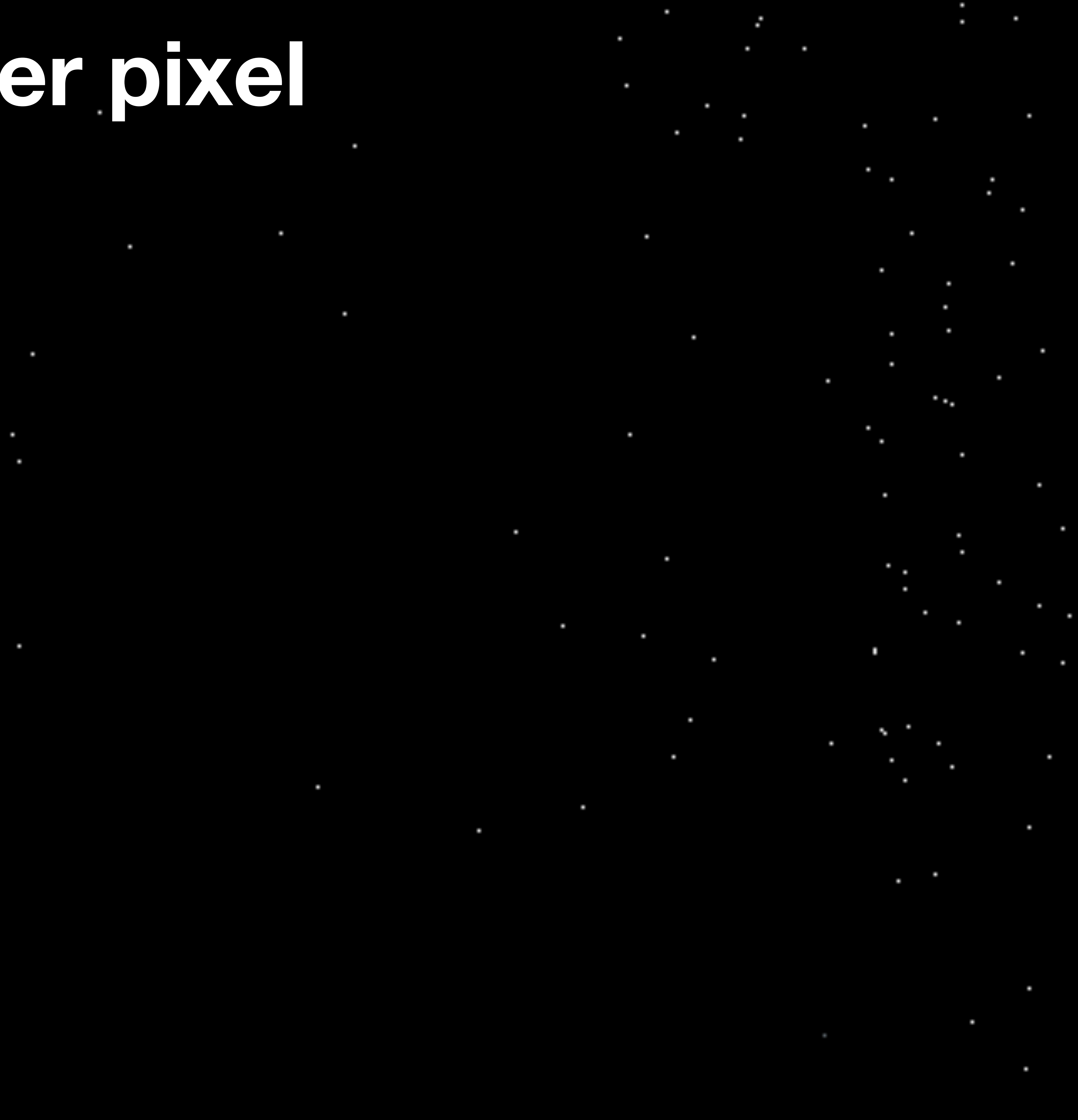


Neural network

Optimize

1 path per pixel

Path tracing



Neural path guiding

2 paths per pixel

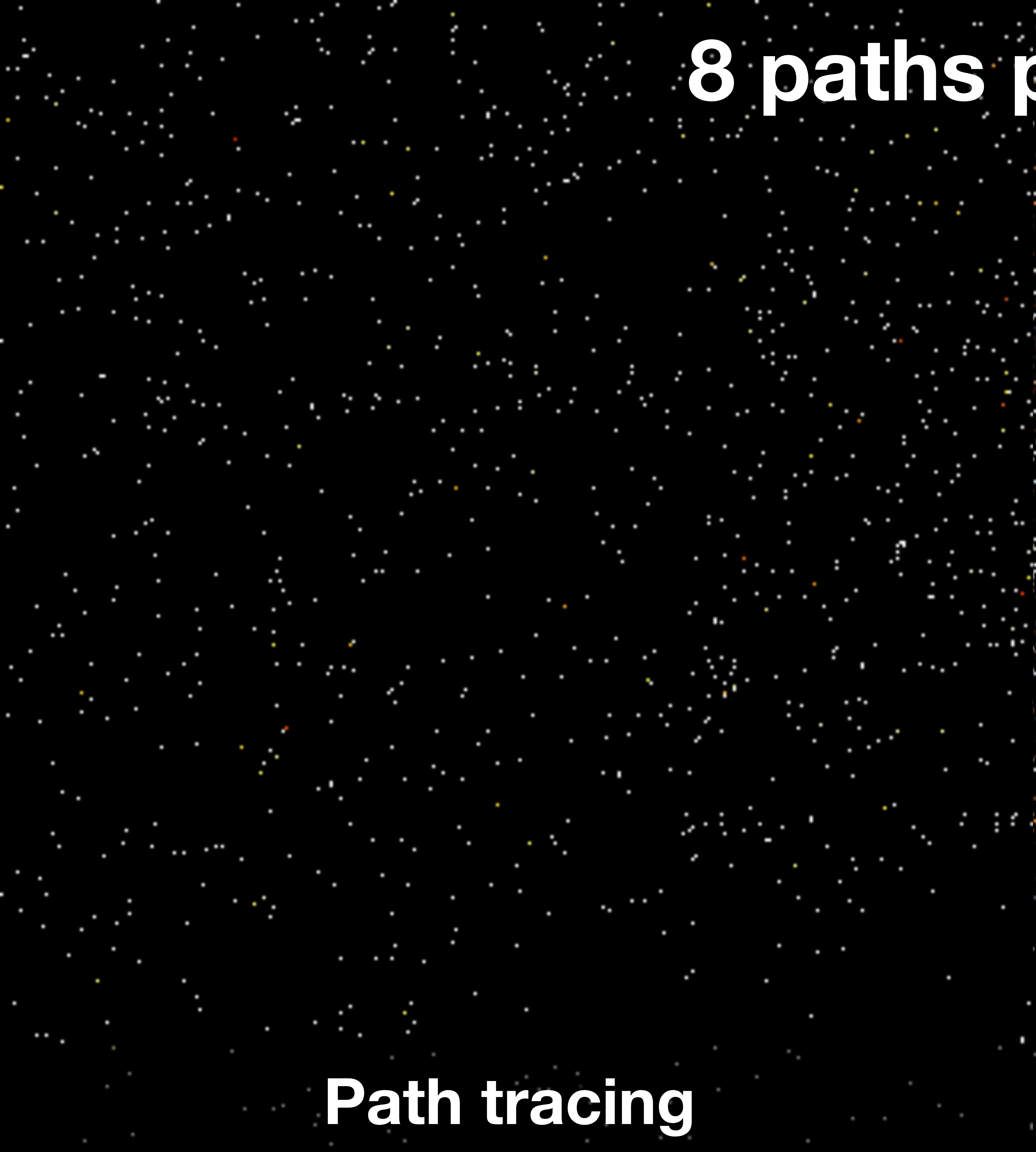
Path tracing **Neural path guiding**

4 paths per pixel

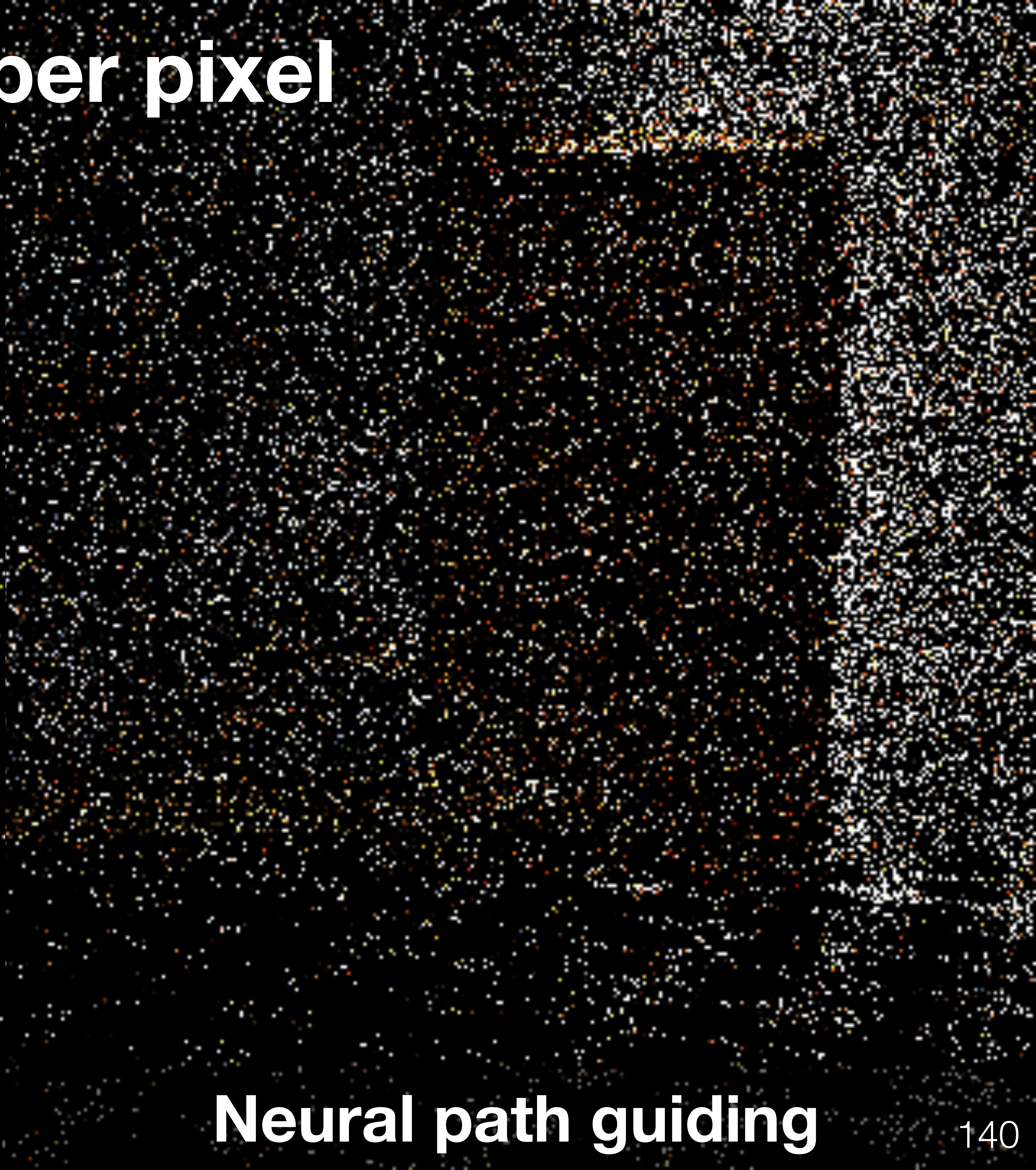
Path tracing

Neural path guiding

8 paths per pixel



Path tracing



Neural path guiding


16 paths per pixel
Path tracing
Neural path guiding

32 paths per pixel

Path tracing

Neural path guiding

64 paths per pixel


128 paths per pixel
Path tracing
Neural path guiding

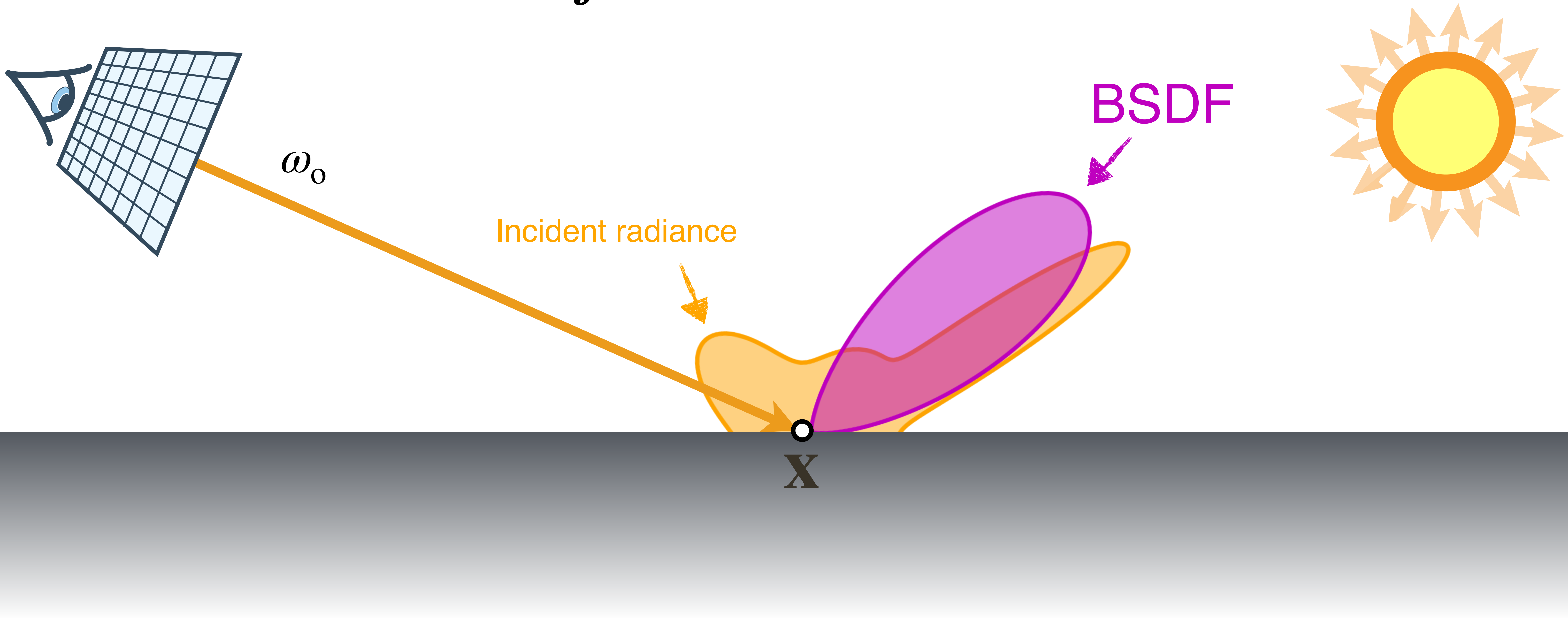

256 paths per pixel
Path tracing
Neural path guiding

512 paths per pixel

Product guiding

Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \, d\omega_i$$



Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \; d\omega_i$$

Product path guiding

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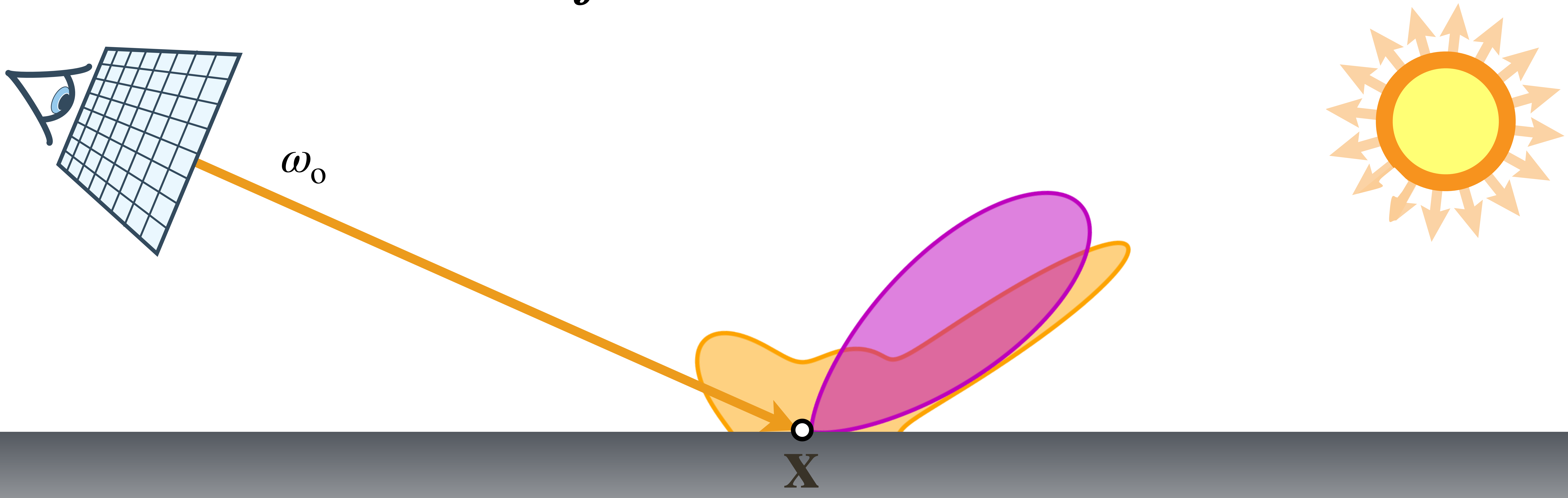
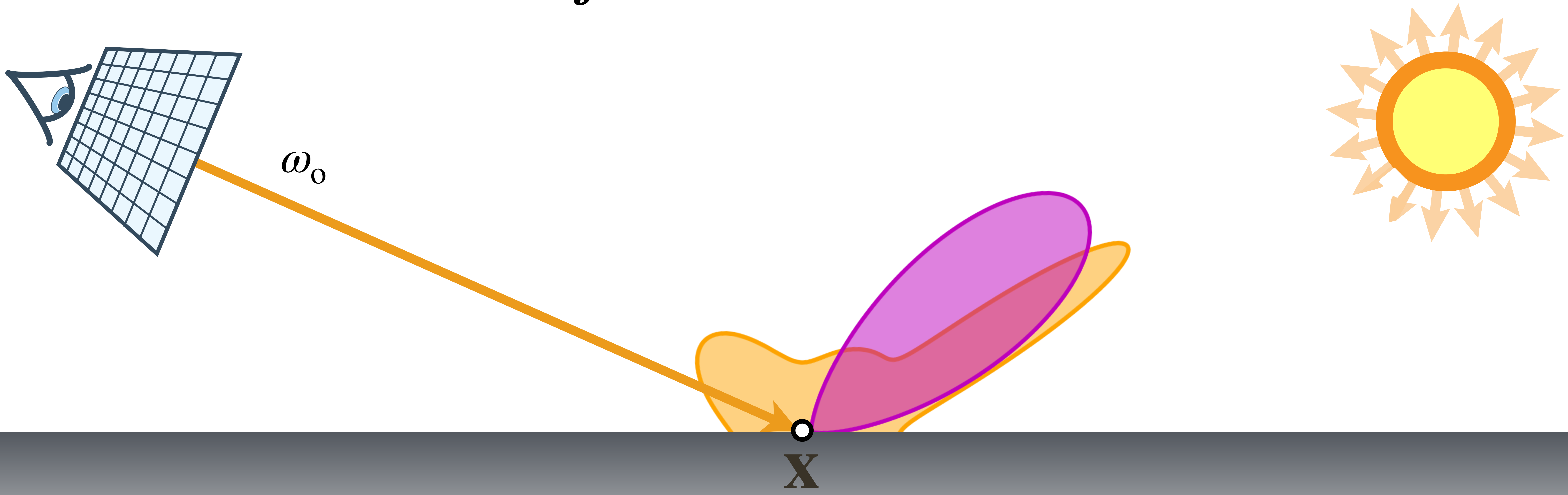


Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \; d\omega_i$$

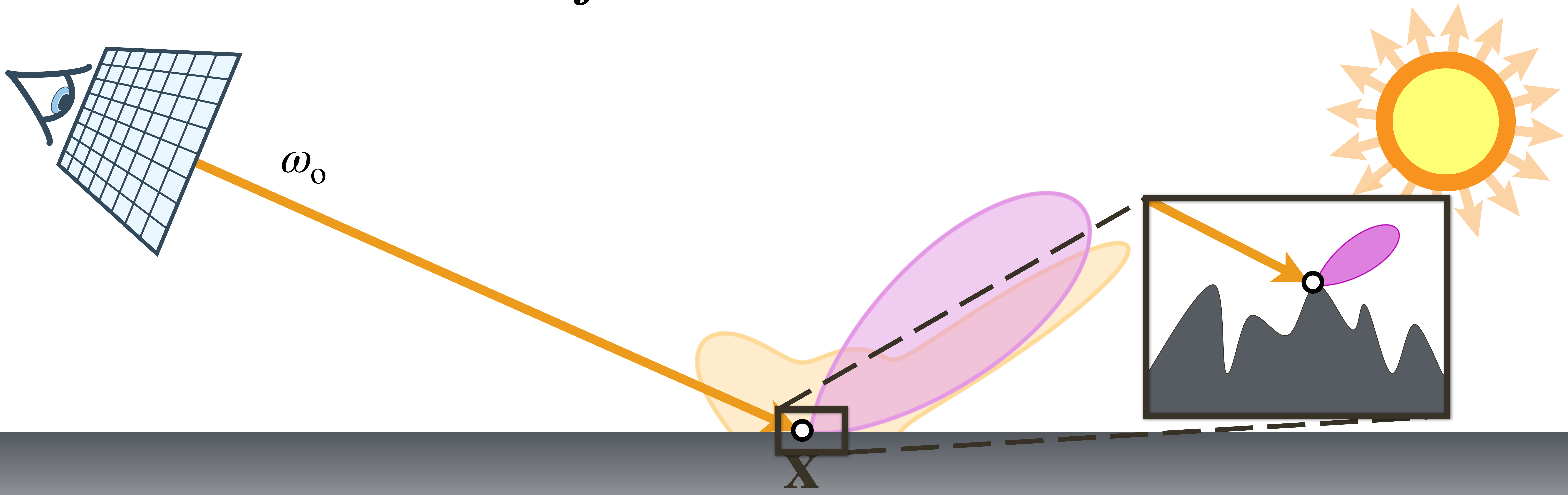
Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \; d\omega_i$$



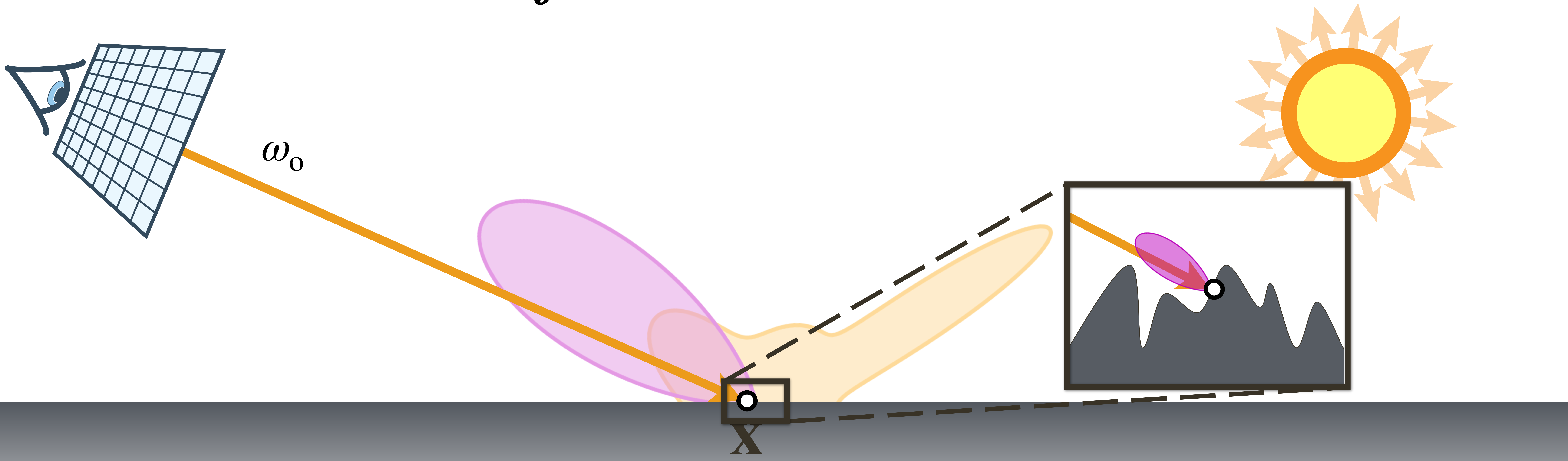
Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \, d\omega_i$$



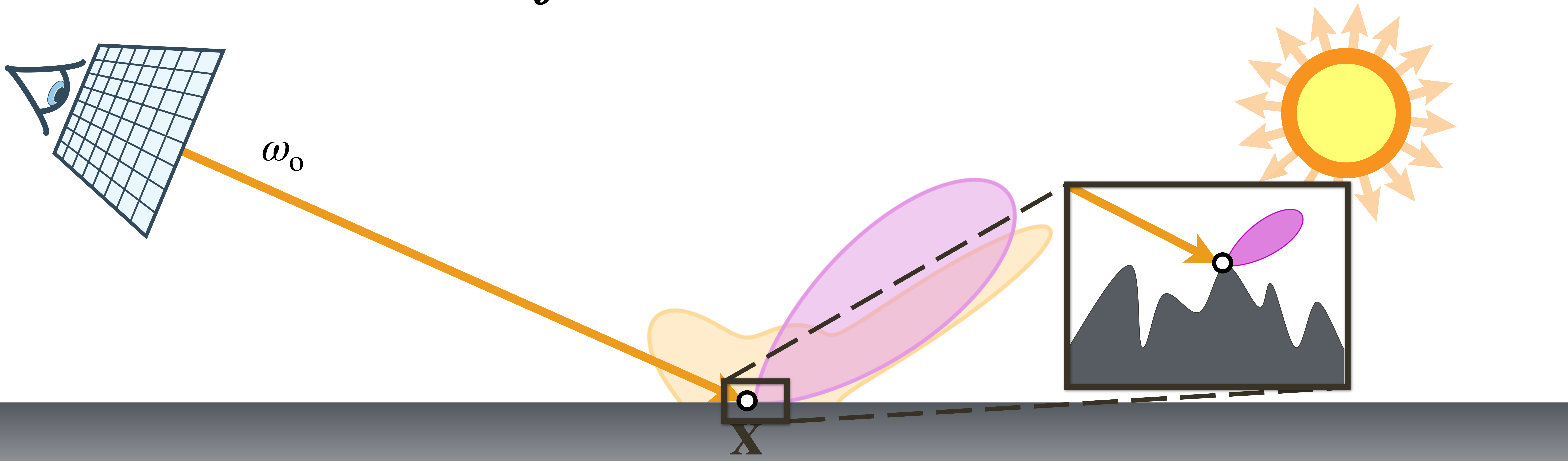
Product path guiding

$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \, d\omega_i$$



Product path guiding

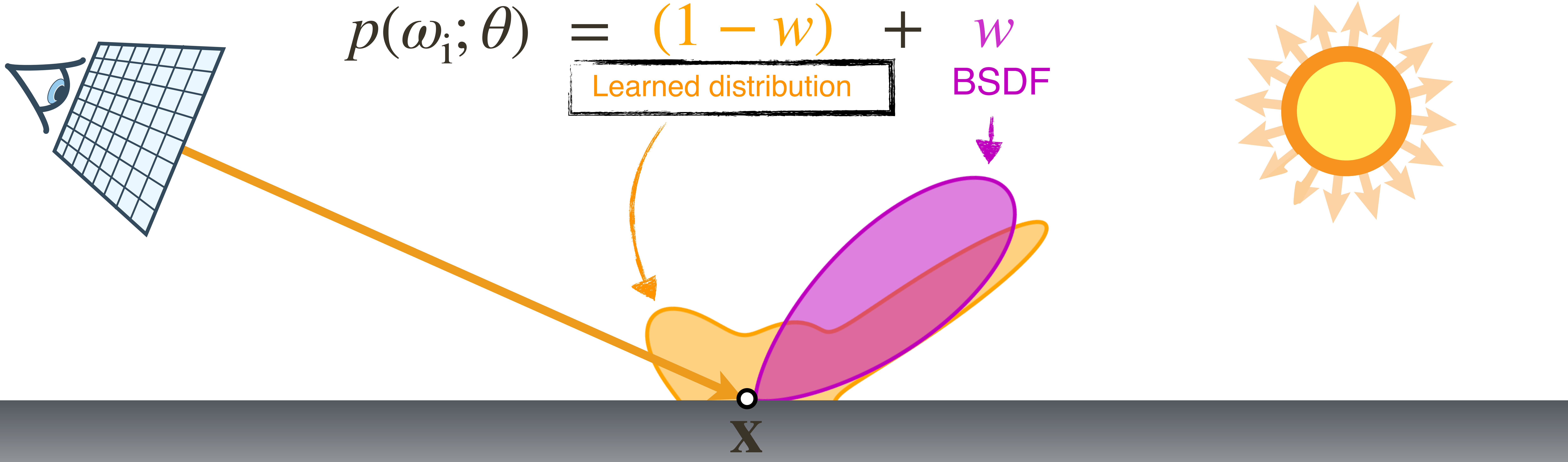
$$L_r(\mathbf{x}, \omega_o) = \int L_i(\mathbf{x}, \omega_i) f(\mathbf{x}, \omega_i, \omega_o) \cos\theta \, d\omega_i$$



MIS optimization

MIS-aware optimization

$$p(\omega_\mathrm{i};\theta) = (1 - w) + w$$

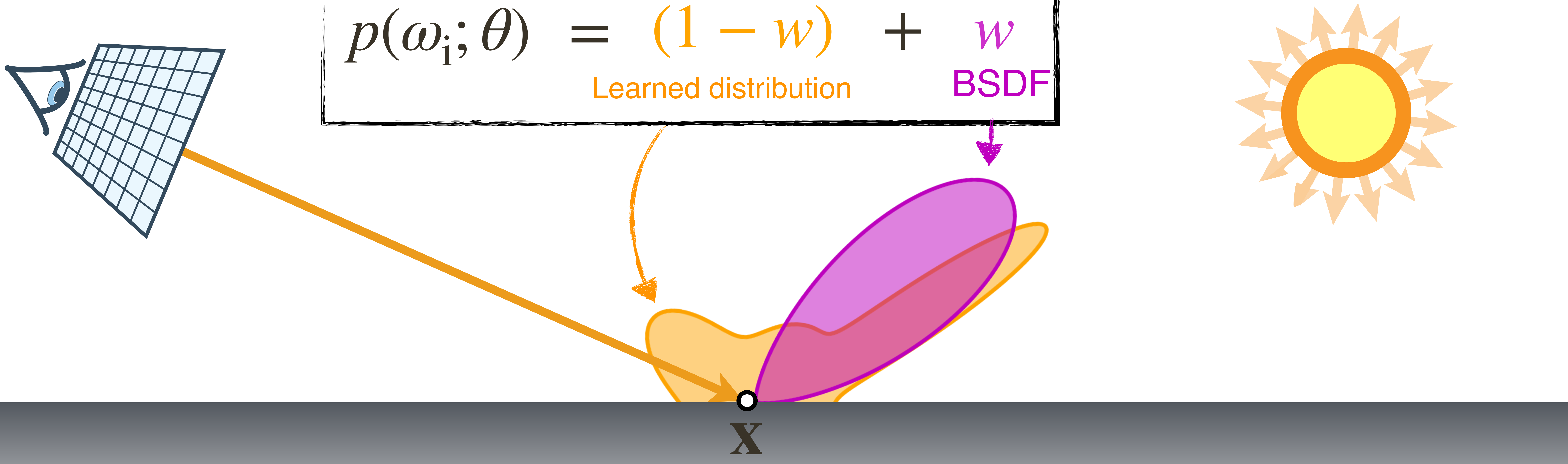


MIS-aware optimization

$$p(\omega_i;\theta) = (1-w) + w$$

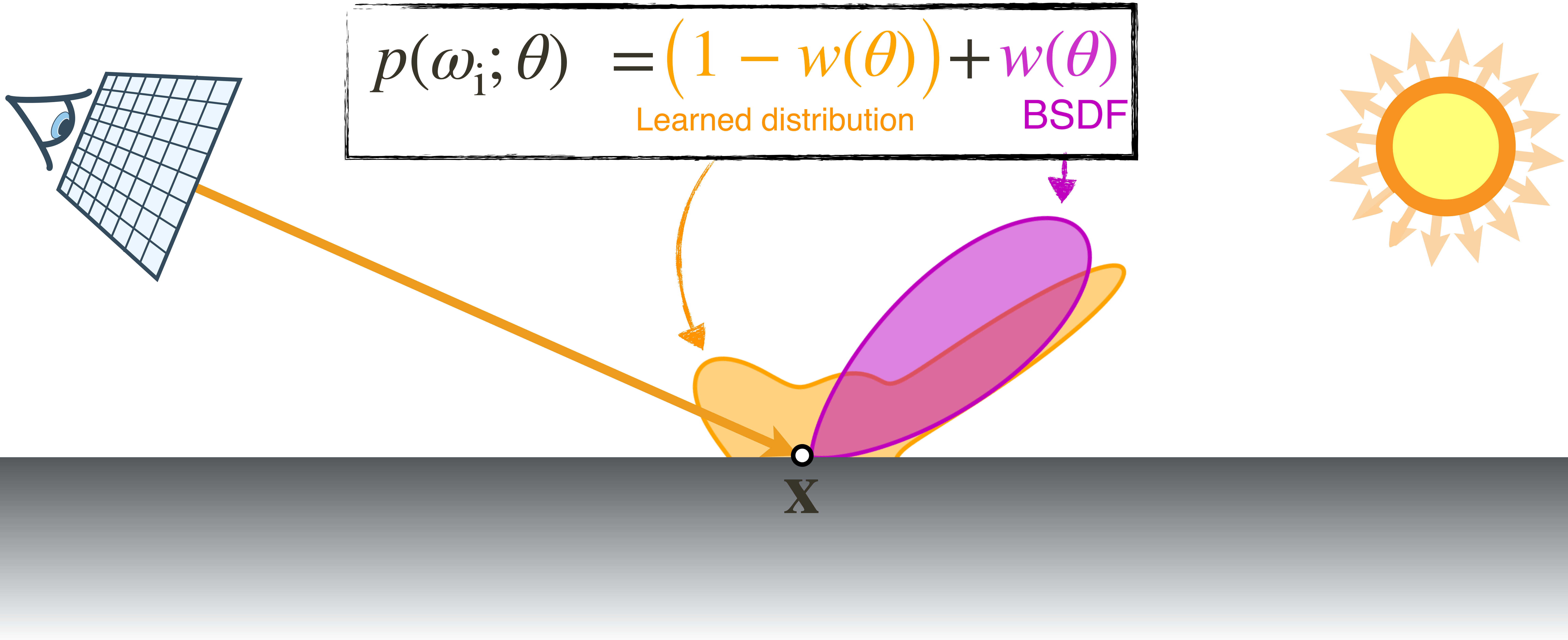
Learned distribution

BSDF



MIS-aware optimization

$$p(\omega_\mathrm{i};\theta) = \left(1 - w(\theta)\right) + w(\theta)$$



Results


Equal time
Path tracing
Müller et al. [2017]
Neural path guiding


Equal spp
Path tracing
Müller et al. [2017]
Neural path guiding


Equal spp
Path tracing
Müller et al. [2017]
Neural path guiding

Conclusion

- Neural networks can drive unbiased MC integration
- Complicated integrands (e.g. product path guiding)
- Computational cost of neural path guiding is high, but quality is state of the art

References

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On Filtering the Noise from the Random Parameters in Monte Carlo Rendering, Sen and Darabi 2012

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Kernel-Predicting Convolutional Networks for Denoising Monte Carlo Renderings, Bako et al. SIGGRAPH 2017

Sample-based Monte Carlo Denoising using a Kernel-Splatting Network, Gharbi et al. SIGGRAPH 2019

NICE: Non-linear Independent Components Estimation

Normalizing Flows: An Introduction and Review of Current Methods

Neural Importance Sampling SIGGRAPH 2019

Acknowledgements

I would like to thank Thomas Muller and colleagues to make their slides available online