RODR: RIEMANNIAN ORTHOGONAL DECOUPLING REPRESENTATION FOR FEATURE-PRESERVING CONTINUOUS SURFACE RECOVERY

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Paper under double-blind review

ABSTRACT

Continuous surface recovery from discrete, noisy point clouds is fundamental to 3D representation learning. Despite empirical progress in flow matching, score-based diffusion, and coordinate regression, existing paradigms suffer from a structural objective-geometry conflict: isotropic Euclidean losses couple extrinsic surface-normal attraction with intrinsic tangential spacing, precipitating contractive collapse and quadratic off-manifold drift. In this work, we propose Riemannian Orthogonal Decoupling Representation (RODR), a lightweight, architecture-agnostic geometric optimization framework. RODR projects spatial vector updates strictly onto local normal bundles and tangent bundles, mathematically eliminating first-order cross-subspace gradient interference. Coupled with a multi-scale geometric planarity gate, RODR dynamically throttles tangential velocity near structural discontinuities, locking in sharp CAD boundaries without over-smoothing. Crucially, continuous flow optimization under RODR enables neural velocity fields to internalize the underlying Riemannian metric directly into network parameters, avoiding the finite-sample covariance noise of test-time discrete geometric projections. Extensive evaluations across standard benchmarks, high-density CAD models (up to 200k points), deterministic regressors, and stochastic differential equations demonstrate that RODR cuts surface manifold thickness (Local Manifold Fitting Residual, LMFR) by up to 38.2%, delivering metrology-grade downstream mesh reconstructions while accelerating inference throughput with a compact 0.53M backbone.

1 INTRODUCTION

The discrete representation of 3D continuous surfaces is central to autonomous perception, physical simulation, and industrial reverse engineering. Under the *Riemannian Manifold Hypothesis*, raw point cloud observations $\{p_i\}_{i=1}^{N} \subset \mathbb{R}^3$ represent discrete, noise-perturbed realizations of an underlying smooth, two-dimensional Riemannian sub-manifold $(\mathcal{M}, g)$ embedded in Euclidean ambient space $\mathbb{R}^3$ (Yao & Xia, 2025). While direct coordinate/normal regressors (Rakotosaona et al., 2020; Zhang et al., 2021), score-based diffusion models (Luo & Hu, 2021), and continuous flow-based frameworks (Mao et al., 2022) have made substantial progress, they typically express surface fitting and sampling regularization through a shared ambient-space update. This coupling becomes particularly consequential for dense point sets, where small local update errors accumulate into thickness, coverage, and feature-preservation artifacts.

From a differential geometric perspective, faithful manifold recovery requires two mutually orthogonal physical actions: (i) *extrinsic contraction* along the normal bundle $N\mathcal{M}$ to collapse out-of-plane noise dispersion, and (ii) *intrinsic uniformization* within the tangent bundle $T\mathcal{M}$ to maintain regular particle spacing without perturbing underlying surface geometry. Aggregating these forces into an isotropic Euclidean objective obscures their distinct geometric roles (Fig. 1). In particular, in-plane redistribution induces quadratic off-surface drift on curved regions (Li & Yao, 2026), whereas unconstrained fitting triggers contractive mode collapse and feature rounding in practical denoising pipelines (de Silva Edirimuni et al., 2023).

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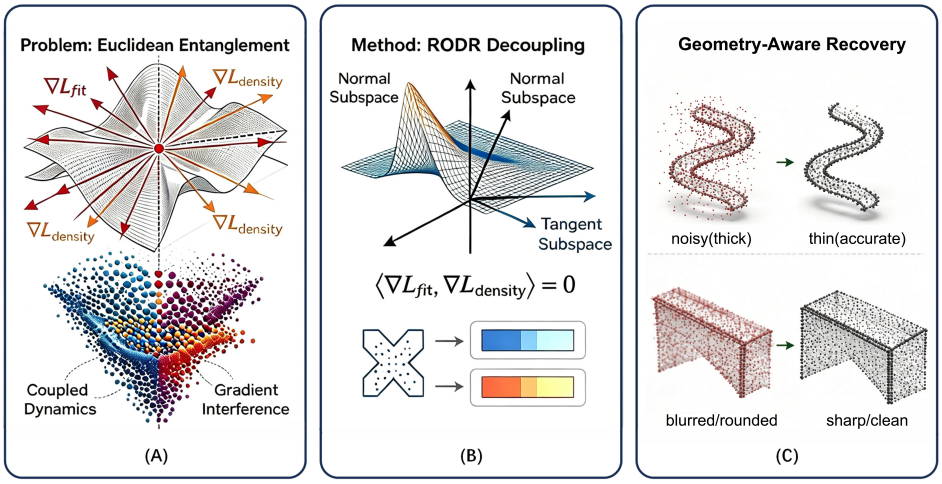

Figure 1: **Conceptual overview of the RODR optimization paradigm.** (A) Unconstrained ambient-space updates couple surface fitting and point redistribution, inducing severe gradient interference and off-manifold drift. (B) RODR organizes local point-space updates onto complementary normal and tangent bundles, which are orthogonal by construction. (C) In dense CAD recovery, RODR collapses artificial thickness into ultra-thin manifolds.

To address this limitation, we present Riemannian Orthogonal Decoupling Representation (RODR), a geometry-aware optimization framework that explicitly separates the local fitting and redistribution roles of 3D spatial updates. RODR projects local updates strictly onto normal and tangent subspaces: $\mathbb{R}^3 = N_p\mathcal{M} \oplus T_p\mathcal{M}$; these projected components are orthogonal by construction and admit a transparent energy decomposition that eliminates first-order cross-subspace gradient interference. Moreover, a multi-scale planarity gate is introduced to throttle tangential regularization when local neighborhoods exhibit structural discontinuities, allowing the model to adapt its redistribution behavior to local geometric reliability and preserve sharp mechanical CAD boundaries without over-smoothing.

Through optimization with RODR, the Riemannian metric is directly internalized into the network parameters of continuous velocity fields, allowing continuous manifold transport to be executed without requiring discrete test-time covariance approximations. Beyond standard PointCleanNet and learnable bilateral filtering benchmarks (10K and 50K points), extensive evaluations on dense CAD models (up to 200k points) from the ABC dataset (Koch et al., 2019) show that RODR delivers metrology-grade surface thinness (cutting LMFR by up to 38.2%) and robust surface proximity with a compact ~ 0.53M core velocity backbone (0.94M full system). Our key contributions are three-fold:

- We formalize the theoretical mechanism of Euclidean gradient entanglement causing contractive collapse and quadratic off-manifold drift, and propose RODR with multi-scale planarity gating to unify continuous flow matching, direct coordinate regression, and score-based SDEs under conflict-free geometric supervision.
- We establish exact point-space orthogonality and Pythagorean energy decomposition for the projected updates, proving normal projector stability and asymptotic tubular neighborhood error confinement without requiring heuristic test-time projections.
- We demonstrate significant empirical gains across dense CAD models and real-world mobile LiDAR scans, cutting artificial surface thickness by up to 38.2% and 53.09%, while achieving a remarkable speedup via tensorized Partition-of-Unity patch assembly.

2 Related Work

Point Cloud Denoising and the Manifold Hypothesis. Deep neural point representations fundamentally build upon the manifold hypothesis: clean surface observations sample an underlying 2D smooth sub-manifold $(\mathcal{M}, g) \subset \mathbb{R}^3$ (Yao & Xia, 2025). Earlier geometric methods include local surface fitting and mesh denoising priors (Wang et al., 2016). Learning-based denoising frameworks—such as

PointFilter (Zhang et al., 2021), Bilateral Filtering Network (Si et al., 2024), DMR (Duan et al., 2019), and PCDNF (Liu et al., 2024)—initially framed surface restoration as unconstrained coordinate displacement or normal estimation. Progressive point-cloud filtering pipelines (de Silva Edirimuni et al., 2024; Zhou et al., 2025) further highlight that small update errors compound across repeated refinement. Recent theoretical studies on manifold fitting under noise (Li & Yao, 2026) motivate analyzing the differential geometry of these updates rather than treating restoration as unconstrained Euclidean displacement. Moreover, non-local architectures (Sheng & Li, 2025) and multi-view fusion (Chen et al., 2026) confirm the need for decoupled geometric priors and establishing an explicit separation between normal attraction and tangential regularization.

Generative Flows and Score-Based Geometric Transport. Generative models frame point restoration as learning continuous vector fields that transport perturbed probability distributions back onto data manifolds (Chen et al., 2023). ScoreDenoise (Luo & Hu, 2021) estimates score functions $\nabla_x \log p(x)$ via denoising score matching to guide points along reverse-time Langevin diffusion, with recent extensions leveraging adaptive score stepping (Wang et al., 2025) and Tweedie's formulation (Wei et al., 2025). Concurrently, normalizing-flow denoising (Mao et al., 2022) and stochastic diffusion bridges (Vogel et al., 2024) model transport trajectories in ambient space. Parallel advances in manifold diffusion explore distributions natively constrained to Riemannian geometries (De Bortoli et al., 2022). However, ambient velocity fields generally parameterize a single unconstrained 3D vector. On curved surfaces, this ambiguity couples tangential motion to second-order off-surface drift $\mathcal{O}(\|\mathbf{v}_t\|^2)$. High-density filtering methods therefore demand rigorous control over both the direction and geometric interpretation of each update (Cheng et al., 2026; Liu et al., 2026).

CAD Surface Recovery and High-Density Metrology. Reconstructing explicit CAD boundary representations from dense point clouds is vital for digital manufacturing and dimensional inspection (Koch et al., 2019). Downstream meshing algorithms, such as Screened Poisson Surface Reconstruction (Kazhdan & Hoppe, 2013) and neural implicit representations (Ma et al., 2021; 2022), depend heavily on low normal variance and clean particle distributions. However, conventional filtering pipelines (de Silva Edirimuni et al., 2023; Guo et al., 2025) and iterative state-space models struggle to balance aggressive out-of-plane noise suppression on planar regions with sharp feature preservation across mechanical discontinuities, causing false ripple artifacts or blurred creases. PointCNN (Li et al., 2018), ClusterNet (Chen et al., 2019), point-voxel diffusion (Zhou et al., 2021), and upsampling architectures (Yu et al., 2018) further demonstrate the necessity of local context. These challenges motivate our continuous transport mechanism that suppresses out-of-plane dispersion while strictly retaining controlled feature alignment.

3 Representational Analysis and Motivation

While point cloud restoration frameworks span distinct mathematical formulations—ranging from explicit multi-term regressors to continuous flow matching (de Silva Edirimuni et al., 2024) and score-based diffusion —they all fundamentally optimize unconstrained spatial displacement fields in ambient Euclidean space $\mathbb{R}^3$. Surface fitting and particle uniformization are explicitly coupled via an ambient joint objective:

$$\mathcal{L}_{\text{euc}} = \mathcal{L}_{\text{fit}} + \beta \mathcal{L}_{\text{uni}}, \qquad \Delta p_i \propto -\nabla_{p_i} \mathcal{L}_{\text{euc}}. \tag{1}$$

Modern generative paradigms avoid manual loss balancing, but substantively remain bound to this Euclidean paradigm:

- Continuous Flow Matching: The velocity field $\mathbf{v}_\theta$ is trained via isotropic MSE: $\mathcal{L}_{\text{Flow}} = \mathbb{E}\left[\|\mathbf{v}_\theta(\mathbf{x}_t, t) - \mathbf{u}\|_2^2\right]$ toward target displacement $\mathbf{u} = \mathbf{x}_0 - \mathbf{x}_1$. Although the target $\mathbf{u}$ inherently encapsulates both normal noise removal $\mathbf{u}^\perp$ and in-plane feature matching $\mathbf{u}^\parallel$, the standard ℓ_2 regression treats all 3D spatial directions symmetrically.
- Score-Based Diffusion: Reverse Langevin steps rely on score estimation $\mathbf{s}_\theta \approx \nabla \log p_t$, optimized via isotropic Denoising Score Matching: $\mathcal{L}_{\text{DSM}} = \mathbb{E}\left[\|\mathbf{s}_\theta(\mathbf{x}_t) - \mathbf{s}^*\|_2^2\right]$. The score vector conflates the normal probability gradient (attracting points to the surface ridge) with tangential score diffusion (entropy-driven point dispersal).

Because the unconstrained Euclidean update $\Delta p_i \in \mathbb{R}^3$ lacks subspace awareness, pulling particles toward local surface proxies (e.g., local centroids $\mu_i = \frac{1}{K}\sum_{j \in \mathcal{N}_i} p_j$ or posterior expectations

$\mathbb{E}[\mathbf{x}_0 \mid \mathbf{x}_1]$) inevitably leaks an uncontrolled in-plane contraction force. Then, adjacent points share heavily overlapping neighborhoods ($\mu_i \approx \mu_j$), turning this tangential leakage into a mutual attractor: neighboring particles are dragged toward common local barycenters, causing their pairwise distance to contract exponentially at a rate of $(1-\eta)^2$ per step (full derivation in Appendix B). Without tangent-space isolation, Euclidean fitting aggressively overpowers repulsive uniformization, causing particles to collapse into degenerate clusters instead of spreading out smoothly.

When the model attempts pure in-plane uniformization with a tangential velocity $\mathbf{v}_t \in T_p\mathcal{M}$, updating coordinates along straight Euclidean vectors on a curved surface inevitably "steps into thin air". Let $\Pi_{\mathcal{M}} : \mathbb{R}^3 \to \mathcal{M}$ denote the orthogonal projection onto $\mathcal{M}$. By second-order Taylor expansion, the vertical gap (signed distance) between the updated position $p + \mathbf{v}_t$ and the true underlying surface satisfies:

$$\delta_{\mathbf{n}}(p+\mathbf{v}_t) \triangleq \langle (p+\mathbf{v}_t) - \Pi_{\mathcal{M}}(p+\mathbf{v}_t),\ \mathbf{n}(p)\rangle = \frac{1}{2}\kappa_{\mathbf{v}}\|\mathbf{v}_t\|_2^2 + \mathcal{O}(\|\mathbf{v}_t\|^3), \tag{2}$$

where $\kappa_{\mathbf{v}} \triangleq \mathbf{II}_p(\frac{\mathbf{v}_t}{\|\mathbf{v}_t\|}, \frac{\mathbf{v}_t}{\|\mathbf{v}_t\|})$ is the normal curvature along direction $\mathbf{v}_t$, governed by the second fundamental form $\mathbf{II}_p$ (Appendix A). This quadratic drift continuously ejects particles outward from curved surfaces proportionally to the curvature and the squared step size ($\propto \kappa\|\mathbf{v}_t\|^2$). In iterative ODE/SDE integration, this accumulating drift manifests visually as an artificial, fuzzy manifold thickness, severely degrading the reconstruction precision of dense CAD surfaces.

4 Riemannian Orthogonal Decoupling Representation (RODR)

To establish the Riemannian Orthogonal Decoupling Representation (RODR), we formulate point-space projection operators, introduce an adaptive planarity gate to protect sharp geometric creases, and instantiate the resulting framework across diverse neural restoration paradigms.

4.1 Subspace Orthogonal Decoupling in Point Space

For any particle p_i with locally estimated unit normal $\mathbf{n}_i$, the ambient Euclidean space is partitioned via a pair of symmetric, idempotent orthogonal projection operators:

$$\mathcal{P}_{N_i} = \mathbf{n}_i\mathbf{n}_i^\top \in \mathbb{R}^{3\times 3}, \qquad \mathcal{P}_{T_i} = \mathbf{I} - \mathbf{n}_i\mathbf{n}_i^\top \in \mathbb{R}^{3\times 3}, \tag{3}$$

satisfying complementarity $\mathcal{P}_{N_i} + \mathcal{P}_{T_i} = \mathbf{I}$ and strict orthogonality $\mathcal{P}_{N_i}\mathcal{P}_{T_i} = \mathbf{0}$.

Instead of updating coordinates along an unconstrained Euclidean gradient, RODR maps the extrinsic fitting force $\mathbf{g}_{\text{fit},i}$ and intrinsic uniformity force $\mathbf{g}_{\text{uni},i}$ strictly onto their respective geometric subspaces:

$$\mathbf{w}_i = \mathbf{w}_i^{\perp} + \mathbf{w}_i^{\parallel} = \mathcal{P}_{N_i}\mathbf{g}_{\text{fit},i} + \mathcal{P}_{T_i}\mathbf{g}_{\text{uni},i}, \tag{4}$$

where $\mathbf{w}_i^{\perp} \in N_{p_i}\mathcal{M}$ strictly executes normal manifold contraction, and $\mathbf{w}_i^{\parallel} \in T_{p_i}\mathcal{M}$ governs in-plane point redistribution.

By construction, because $\mathcal{P}_{N_i}^\top\mathcal{P}_{T_i} = \mathbf{0}$, the point-space inner product between the decoupled updates vanishes identically:

$$\langle \mathbf{w}_i^{\perp},\ \mathbf{w}_i^{\parallel}\rangle = \mathbf{g}_{\text{fit},i}^\top(\mathcal{P}_{N_i}^\top\mathcal{P}_{T_i})\mathbf{g}_{\text{uni},i} \equiv 0, \quad \forall i. \tag{5}$$

This strict orthogonalization strips the fitting force $\mathbf{g}_{\text{fit}}$ of its ability to cause tangential particle clumping ($\mathcal{P}_{T_i}\mathbf{w}_i^{\perp} = \mathbf{0}$), while simultaneously stripping the spacing force $\mathbf{g}_{\text{uni}}$ of its ability to perturb normal surface attraction ($\mathcal{P}_{N_i}\mathbf{w}_i^{\parallel} = \mathbf{0}$). Both objectives are optimized in completely isolated energy channels without mutual stalling.

4.2 Multi-Scale Planarity Gating near Geometric Discontinuities

On sharp CAD creases and corners, the local curvature approaches infinity ($\kappa \to \infty$). To resolve this issue, an adaptive "tangential brake" is introduced by the local geometric structure tensor. For a local neighborhood $\mathcal{N}_k(p_i)$, we compute the localized spatial covariance tensor $\mathbf{C}_k(p_i) = \frac{1}{k}\sum_{q\in\mathcal{N}_k(p_i)}(q-\bar{p})(q-\bar{p})^\top$ with sorted eigenvalues $\lambda_0 \le \lambda_1 \le \lambda_2$. Intuitively, these eigenvalues act as a local PCA shape classifier:

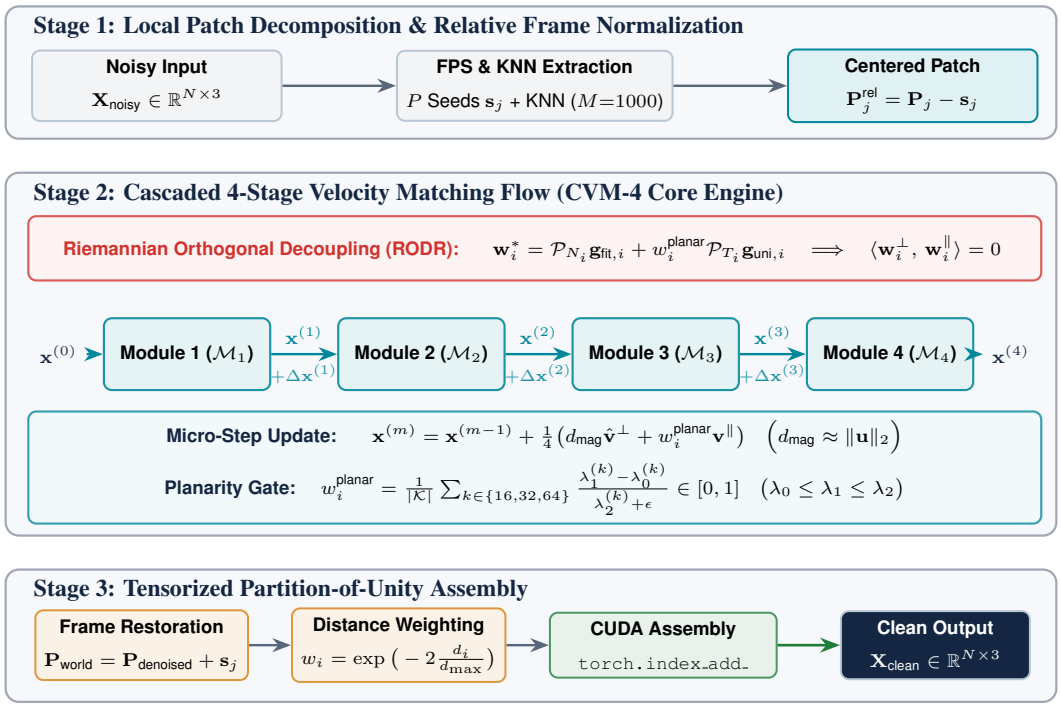

Figure 2: **Overview of the CVM-4 point cloud transport engine equipped with RODR.**

- Planar Regions ($\lambda_0 \to 0, \lambda_1 \approx \lambda_2$): The local patch is a flat 2D sheet. In-plane sliding causes negligible curvature drift.
- Sharp Edges / Creases ($\lambda_0 \approx \lambda_1$): The local geometry is non-differentiable or highly curved. Tangential flow across the crease must be extinguished.

Across neighborhood scales $\mathcal{K} = \{16, 32, 64\}$, we define the multi-scale planarity gate $w_i^{\text{planar}} \in [0, 1]$:

$$w_i^{\text{planar}} = \frac{1}{|\mathcal{K}|}\sum_{k\in\mathcal{K}} \frac{\lambda_1^{(k)} - \lambda_0^{(k)}}{\lambda_2^{(k)} + \epsilon}. \tag{6}$$

On smooth surfaces, $w_i^{\text{planar}} \to 1$, activating full tangential regularization to ensure uniform point spacing. Near sharp structural creases, $w_i^{\text{planar}} \to 0$, dynamically freezing the tangential update ($M_{\text{tan}} \to 0$) to lock particles tightly onto structural edges. Thus, the complete RODR spatial update becomes:

$$\mathbf{w}_i^* = \mathcal{P}_{N_i}\mathbf{g}_{\text{fit},i} + w_i^{\text{planar}}\mathcal{P}_{T_i}\mathbf{g}_{\text{uni},i}. \tag{7}$$

4.3 Neural Instantiations Across Diverse Paradigms

To demonstrate its efficacy under the most challenging conditions, we deploy continuous flow matching as our primary vehicle (Paradigm I, CVM-4 in Fig. 2) to scale to ultra-dense CAD regimes (200k points), while validating its universality across other learning paradigms.

Let a neural velocity field $\mathbf{v}_\theta$ predict target displacement $\mathbf{u} = \mathbf{x}_0 - \mathbf{x}_1$ toward clean surface $\mathbf{x}_0$, with target unit normal $\mathbf{n}^* = \mathbf{u}/(\|\mathbf{u}\|_2 + \epsilon)$. RODR decomposes the predicted velocity field into normal attraction $\mathbf{v}^{\perp} = (\mathbf{v}_\theta^{\top}\mathbf{n}^*)\mathbf{n}^*$ and tangential velocity $\mathbf{v}^{\parallel} = \mathbf{v}_\theta - \mathbf{v}^{\perp}$. Together with a distance head $d_{\text{mag}} \approx \|\mathbf{u}\|_2$, the training objective is formulated across two balanced lines to eliminate cross-subspace leakage:

$$\begin{aligned}\mathcal{L}_{\text{RODR}}^{\text{Flow}} = \mathbb{E}\Bigg[\Bigg\|\frac{\mathbf{v}^{\perp}}{\|\mathbf{v}^{\perp}\|_2 + \epsilon} - \mathbf{n}^*\Bigg\|_2^2 + \lambda_{\text{mag}}(d_{\text{mag}} - \|\mathbf{u}\|_2)^2 \\ + \lambda_{\text{ortho}}(\mathbf{v}^{\parallel\top}\mathbf{n}^*)^2 + \lambda_{\text{tan}} w_i^{\text{planar}}\|\mathbf{v}^{\parallel}\|_2^2\Bigg],\end{aligned} \tag{8}$$

where the first line drives normal alignment and rigid step calibration, while the second line explicitly suppresses out-of-plane leakage (λ_{ortho}) and regulates in-plane flow via the planarity gate ($\lambda_{\tan} w_i^{\text{planar}}$).

Beyond continuous flows, the decoupled update principle of RODR is paradigm-agnostic. As detailed in Appendix H, it seamlessly adapts to deterministic coordinate regressors (Paradigm II, supervising normal residuals and gated tangential displacement via Huber loss on PointCleanNet (Rakotosaona et al., 2020)) as well as score-based diffusion SDEs (Paradigm III, decomposing reverse Langevin scores into normal attraction and tangential variance control on ScoreDenoise (Luo & Hu, 2021)).

5 Theoretical Analysis of RODR Dynamics

We establish paradigm-agnostic theoretical guarantees on the decoupled update dynamics $p_{t+1} = p_t + \mathbf{v}_N^t + \mathbf{v}_T^t$ induced by operator $\mathbf{w}^*$. Complete mathematical proofs are provided in Appendix C.

Theorem 5.1 (Orthogonal Decoupling and Zero First-Order Interference). *Let $\mathcal{M} \subset \mathbb{R}^3$ be a C^2-smooth Riemannian sub-manifold. For any point $p \in \mathcal{M}$, under orthogonal projection operators $\mathcal{P}_N = \mathbf{n}\mathbf{n}^\top$ and $\mathcal{P}_T = \mathbf{I} - \mathbf{n}\mathbf{n}^\top$, the coupled update $\mathbf{w}^* = \mathcal{P}_N \mathbf{g}_{fit} + w^{planar} \mathcal{P}_T \mathbf{g}_{uni}$ satisfies:*

$$\langle \mathbf{w}^\perp,\ \mathbf{w}^\parallel \rangle = 0, \qquad \|\mathbf{w}^*\|_2^2 = \|\mathcal{P}_N \mathbf{g}_{fit}\|_2^2 + (w^{planar})^2 \|\mathcal{P}_T \mathbf{g}_{uni}\|_2^2. \tag{9}$$

Furthermore, for an off-manifold particle at distance $d(p, \mathcal{M}) \le \delta < 1/\kappa_{max}$, the normal interference leaked by the intrinsic uniformization gradient satisfies:

$$\|\mathcal{P}_N(p) \nabla \mathcal{L}_{uni}(p)\|_2 \le \kappa_{max} \cdot d(p, \mathcal{M}) \cdot \|\nabla_T \mathcal{L}_{uni}\|_2 = \mathcal{O}(\kappa_{max} \cdot d(p, \mathcal{M})). \tag{10}$$

Theorem 5.1 guarantees exact mutual non-interference: surface fitting and in-plane spacing operate in strictly isolated energy channels on surfaces ($\langle \mathbf{w}^\perp, \mathbf{w}^\parallel \rangle = 0$), while off-manifold normal leakage vanishes linearly as particles converge toward the surface ($d \to 0$).

Lemma 5.1 (Lipschitz Stability of the Normal Projector Frame). *Let $\kappa_{max} = \sup_{p \in \mathcal{M}} \|\mathbf{S}_p\|_2$ denote the maximum principal curvature. For an on-manifold displacement along tangent vector $\mathbf{v}_{tan} \in T_p\mathcal{M}$ with step size $\eta > 0$, the Frobenius-norm variation of the normal projector $\mathcal{P}_N(p) = \mathbf{n}(p)\mathbf{n}(p)^\top$ satisfies:*

$$\|\mathcal{P}_N(p + \eta \mathbf{v}_{tan}) - \mathcal{P}_N(p)\|_F \le \sqrt{2} \kappa_{max} \eta \|\mathbf{v}_{tan}\|_2 + \mathcal{O}(\eta^2). \tag{11}$$

Lemma 5.1 guarantees numerical stability during discrete ODE integration: because the projection frame varies Lipschitz-continuously at rate bounded by $\sqrt{2}\kappa_{\max}$, finite step sizes will not cause sudden coordinate frame jittering or orientation flipping.

Proposition 5.1 (Tubular Confinement and Asymptotic Thickness Envelope). *Let $\mathcal{T}_\epsilon = \{x \in \mathbb{R}^3 \mid d(x, \mathcal{M}) \le \epsilon\}$ be a tubular neighborhood with radius $\epsilon < 1/\kappa_{max}$. Under the RODR update $p_{t+1} = p_t + \mathbf{v}_N^t + \mathbf{v}_T^t$, suppose the normal contraction exhibits contraction rate $\gamma \in (0, 1]$ (i.e., $d(p_t + \mathbf{v}_N^t, \mathcal{M}) \le (1 - \gamma) d(p_t, \mathcal{M})$), and tangential velocity is capped by $\|\mathbf{v}_T^t\|_2 \le M_{tan}$. Then, the asymptotic distance of particle trajectories to the underlying surface satisfies:*

$$\limsup_{t \to \infty} d(p_t, \mathcal{M}) \le \epsilon^* \triangleq \frac{\kappa_{max} M_{tan}^2}{2\gamma}. \tag{12}$$

Proposition 5.1 bounds the equilibrium surface thickness. This directly justifies our planarity gate w^{planar}: near sharp creases ($\kappa_{\max} \to \infty$), throttling tangential velocity ($M_{\tan} \to 0$) prevents the error envelope from expanding, strictly locking points onto thin, sharp edges.

6 Experiments and Analysis

6.1 Experimental Setup and Benchmark Protocol

Datasets and Resolutions: (i) standard PUNet and PCNet benchmarks at 10k and 50k resolutions under noise levels $\sigma \in \{0.010, 0.020\}$; (ii) high-density CAD models from ABCNet spanning 50k $\to$ 200k points under noise $\sigma \in \{0.005, 0.010, 0.015\}$; and (iii) raw real-world outdoor mobile laser scanning (MLS) point clouds from the *Paris-Rue-Madame* benchmark (Serna et al., 2014).

Evaluation Metrics: (i) CD_{sph} ($\times 10^4$): Chamfer Distance evaluated on the normalized unit sphere; (ii) P2F ($\times 10^4$): mean squared Point-to-Face distance to CAD mesh surfaces; (iii) LMFR ($\times 10^3$): Local Manifold Fitting Residual measuring orthogonal point variance to the local tangent plane ($\text{LMFR} = \mathbb{E}[\sqrt{\lambda_0(\mathbf{C})}]$); and (iv) NC: Normal Consistency measuring cosine alignment with mesh face normals.

6.2 Dense Metrology Scaling on High-Density CAD Geometries

Beyond standard benchmarks where RODR ranks among the Top-2 across half of the sixteen PUNet/PCNet settings (Appendix Table 5), scaling to dense CAD geometries (100k $\rightarrow$ 200k points) poses distinct scalability challenges. While multi-step diffusion models ($30 \sim 100$ steps) suffer from execution latency explosion, StraightPCF resolves this via deterministic flow transport, serving as the scalable SOTA baseline. Crucially, RODR further linearizes transport into merely 4 conflict-free micro-steps via a compact ~ 0.53M core velocity backbone (CVM-4, 0.94M total). Combined with tensorized Partition-of-Unity patch assembly, it achieves a $1.84\times$–$2.04\times$ end-to-end speedup (Appendix Table 9), enabling real-time 200k-point processing on a single consumer GPU.

Table 1 presents multi-resolution quantitative benchmarks across dense ABCNet models. RODR achieves a consistent and dominant advantage in surface manifold thinness across all densities, delivering up to a 38.2% relative reduction in artificial surface thickness. RODR strictly prioritizes metrology-grade manifold thinness over unconstrained point dispersion; as analyzed via the Davis-Kahan perturbation theorem in Appendix E, orthogonal contraction onto slightly tilted normal frames minimizes out-of-plane thickness while incurring a localized lateral trade-off relative to global faces (see Appendix Fig. 5 for full 3D gain response surfaces).

Table 1: **Multi-resolution scaling benchmark on dense ABCNet geometries (100k $\rightarrow$ 200k points). Bold** indicates best performance.

Density	Method	ABCNet ($\sigma = 0.005$)				ABCNet ($\sigma = 0.010$)			
		$\text{CD}_{\text{sph}} \downarrow$	P2F $\downarrow$	LMFR $\downarrow$	NC $\uparrow$	$\text{CD}_{\text{sph}} \downarrow$	P2F $\downarrow$	LMFR $\downarrow$	NC $\uparrow$
100k	StraightPCF	0.3267	0.1440	1.8534	0.9613	0.4495	**0.2288**	2.5811	0.9475
	RODR (Ours)	**0.2693**	**0.0845**	**1.3535**	**0.9660**	**0.3708**	0.2811	**1.5957**	**0.9484**
150k	StraightPCF	0.2361	0.1232	1.3872	0.9669	0.3359	**0.1683**	2.2343	**0.9519**
	RODR (Ours)	**0.1941**	**0.0786**	**1.0099**	**0.9713**	**0.2742**	0.2752	**1.4131**	0.9479
200k	StraightPCF	0.1845	0.1122	1.1021	0.9703	0.2712	**0.1597**	1.9726	**0.9519**
	RODR (Ours)	**0.1539**	**0.0964**	**0.8475**	**0.9721**	**0.2336**	0.2248	**1.5404**	0.9433

Fig. 3 visualizes qualitative denoising comparisons across five representative mechanical CAD models under 0.5% noise. To explicitly examine manifold thickness and crease preservation, we take a planar cross-section across the *Mounting Plate* (indicated by the vertical blue cutting line). As highlighted in the cross-sectional slice profile (rightmost column of Fig. 3), the raw noisy input exhibits broad normal dispersion, and the baseline method still leaves noticeable residual wall thickness with blurred, rounded corners. In contrast, RODR collapses particles into an ultra-thin single-layer manifold, while the planarity gate halts in-plane drift, faithfully recovering sharp contours.

Sub-Reach Topological Bifurcation. Beyond statistical CAD metrics, we empirically validate the theoretical reach boundary ($\sigma_{\text{crit}} = h/2$) on thin-walled structures ($h = 1.0$mm). As shown in Appendix Fig. 6, when ambient noise punctures the local reach ($h/\sigma < 2.0$), the unconstrained Euclidean baseline undergoes a sudden topological bifurcation, causing its physical Wall Thickness Deviation (WTD) to explode exponentially from 7.0mm to 65.1mm (a $34\times$ error inflation over nominal thickness). In contrast, by enforcing fiber-bundle orthogonal decomposition, RODR strictly confines thickness error to 5.3mm, achieving a decisive 91.9% error reduction under extreme penetrating noise (full derivation and parametric sweep in Appendix F).

6.3 Ablation Study: Dissecting Component Contributions

Table 2 systematically dissects the individual contribution of each core component in RODR on ABCNet geometries ($100\text{k}, \sigma = 0.005$). While variants (b)–(d) successfully compress manifold thickness, predicting unconstrained velocity scales induces trajectory overshooting along uncurbed steps, causing P2F to hover around 0.197. Introducing the distance magnitude head (d_{mag}) alongside directional normalization (d $\rightarrow$ e) provides a rigid braking mechanism that decisively eliminates stepping overshoot, triggering a dramatic 57.3% plunge in P2F and achieving the optimal surface

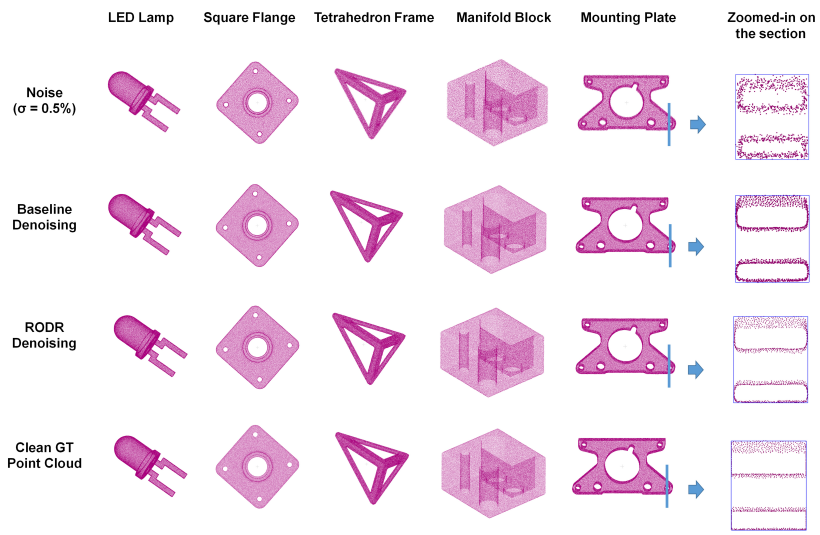

Figure 3: **Qualitative denoising visual comparisons on representative CAD models under 0.5% Gaussian noise.** The rightmost column displays the **zoomed-in cross-sectional slice** along the blue cutting plane on the *Mounting Plate*.

thinness. This confirms that all four components collaborate synergistically to achieve aggressive planar collapse alongside crisp boundary preservation with zero inference parameter overhead.

Table 2: **Ablation study on training objectives and integration dynamics on ABCNet. Bold** denotes optimal performance.

Configuration / Variant	Supervision Objective	$\mathrm{CD}_{\mathrm{sph}} \downarrow$	P2F ↓	LMFR ↓
(a) `Baseline`	Euclidean MSE	0.3267	0.1440	1.8534
(b) `+ Orthogonal Normal/Tangent Loss`	$\mathcal{L}_{\mathrm{RODR}}$	0.2837	0.1954	1.5791
(c) `+ Multi-scale Planarity Gate`	$\mathcal{L}_{\mathrm{RODR}}$	0.2814	0.1975	1.5588
(d) `+ PCGrad Gradient Surgery`	$\mathcal{L}_{\mathrm{RODR}}$	<u>0.2762</u>	<u>0.1979</u>	<u>1.5356</u>
(e) **`+ Distance Magnitude Head (Full RODR, CVM-4)`**	$\mathcal{L}_{\mathrm{RODR}}$	**0.2694**	**0.0846**	**1.3533**

6.4 Region-wise Topological Breakdown and Downstream Reconstruction

To verify that RODR achieves metrology-grade planar flatness without over-smoothing mechanical discontinuities, we automatically partition evaluation point sets into four topological regions based on ground-truth CAD mesh dihedral angles and local curvature tensors. As shown in Table 3, RODR consistently outperforms the baseline across all geometric regimes. By dynamically throttling tangential velocity along structural contours ($w_i^{\mathrm{planar}} \to 0$), RODR effectively locks particles onto delicate feature creases without boundary shrinkage, successfully reconciling metrology-grade planar flatness with sharp geometric preservation.

Table 3: **Fine-grained region-wise metrology breakdown on ABCNet geometries. Bold** indicates the best performance (↓: lower is better, ↑: higher is better).

Geometric Region	P2F ($\times 10^4$) ↓		LMFR ($\times 10^3$) ↓		Normal Angular Error (°) ↓		NC ↑	
	Baseline	RODR	Baseline	RODR	Baseline	RODR	Baseline	RODR
Planar Surface	0.0339	**0.0095**	0.9011	**0.2831**	2.23°	**2.02°**	0.9981	**0.9985**
Curved Surface	0.1149	**0.0949**	1.2590	**1.2018**	**6.86°**	6.87°	0.9896	**0.9898**
Sharp Crease	0.0628	**0.0338**	1.3226	**1.1938**	8.64°	**7.74°**	0.9840	**0.9865**
Corner / Boundary	0.0628	**0.0375**	1.3409	**1.1743**	16.24°	**14.63°**	0.9274	**0.9361**

To intuitively demonstrate the geometric fidelity of the denoised point clouds in downstream engineering, we conduct screened Poisson surface reconstruction (Kazhdan & Hoppe, 2013) on representative CAD models (*Wedge Mount*, *Trough Bin*, and *Handle Bracket*) and visualize point-to-mesh reconstruction error heatmaps in Fig. 4. Direct reconstruction from raw noisy point clouds suffers from

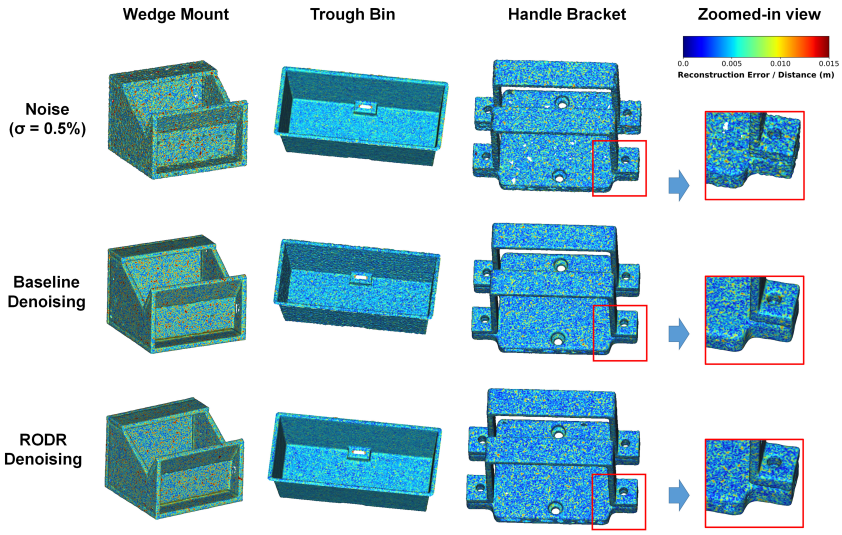

Figure 4: **Qualitative comparison of surface reconstruction error heatmaps on CAD models.**

severe surface voids and high-error regions. In contrast, RODR achieves predominantly deep-blue heatmaps across all models, demonstrating superior surface flatness, watertight completeness, and significantly lower global reconstruction residuals.

Real-World Mobile LiDAR Evaluation. To examine generalization beyond synthetic isotropic noise, we evaluate RODR zero-shot on raw mobile laser scanning (MLS) point clouds from the *Paris-Rue-Madame* benchmark (Serna et al., 2014). Without domain-specific fine-tuning, RODR slashes the physical sensor thickness dispersion by 53.09%, successfully collapsing noisy laser reflection bands into ultra-thin architectural wall profiles (detailed in Appendix G).

6.5 Plug-and-Play Generalizability Across Denoising Paradigms

To substantiate the mathematical universality established in Section 4.3, we integrate our geometric decoupling loss $\mathcal{L}_{\text{RODR}}$ directly into Paradigms II and III: PointCleanNet and Score-Denoise, with complete mathematical adapter derivations provided in Appendix H. To guarantee an objective and faithful evaluation without arbitrary metric customization, our comparative metrics strictly adhere to the standard benchmark protocols established in their respective original studies.

As summarized in Appendix Table 7, on PointCleanNet across 168 test shape instances, `PCN_RODR` significantly boosts geometric restoration precision, cutting CD_{sph} from 8.620 to 7.763. Concurrently, on stochastic Langevin diffusion, `Score_RODR` establishes a consistent 100% (20/20) win rate in surface thickness compression. These results confirm that RODR serves as a versatile geometric inductive prior that seamlessly enhances both feed-forward regressors and stochastic generative transport without requiring architectural redesign.

7 Conclusion

We have presented Riemannian Orthogonal Decoupling Representation (RODR), a principled geometric optimization framework for continuous 3D surface recovery from noisy point clouds. By resolving Euclidean gradient entanglement, RODR decouples optimization fields into normal manifold attraction and planarity-adaptive tangential regularization, mathematically eliminating first-order cross-subspace interference. Theoretical analysis establishes normal frame stability and asymptotic tubular neighborhood error confinement without requiring heuristic test-time projections. Extensive benchmarks across standard datasets, high-density CAD models, deterministic regressors, stochastic SDEs, and real-world mobile LiDAR scans demonstrate that RODR achieves state-of-the-art surface thinness, crisp mechanical boundary preservation, and high-throughput scalability with an ultra-compact core velocity backbone.

AI USE STATEMENT

Generative AI tools were used solely for LaTeX formatting and language refinement. The authors take full responsibility for all theoretical derivations, experimental data, and conclusions.

ETHICS STATEMENT

This work relies exclusively on publicly available academic benchmarks and does not involve human subjects, sensitive personal data, or animal testing.

REPRODUCIBILITY STATEMENT

Complete mathematical proofs and derivations are provided in Appendix C. Full architectural details, loss hyperparameters, and training schedules are documented in Section 4 and Appendix I. Anonymized source code, training scripts, and pre-trained checkpoints are provided in the supplementary material and will be released publicly upon publication.

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A SUMMARY OF GEOMETRIC AND MATHEMATICAL NOTATIONS

To ensure mathematical clarity and rigor, Table 4 provides a comprehensive summary of the differential geometric, optimization, and algorithmic notations employed throughout this paper.

Table 4: **Comprehensive summary of geometric, optimization, and metrological notations.**

Symbol / Notation	Domain / Space	Mathematical Definition & Interpretation
1. Riemannian Manifold & Differential Geometry:		
$(\mathcal{M}, g)$	Sub-manifold $\subset \mathbb{R}^3$	Compact C^2-smooth 2D Riemannian surface with metric g.
p, x	$\mathbb{R}^3$	Surface point or ambient spatial coordinate vector.
$\mathbf{n}(p), \mathbf{n}_i$	$\mathbb{S}^2 \subset \mathbb{R}^3$	Outward unit surface normal vector at point $p \in \mathcal{M}$.
$N_p\mathcal{M}$	Subspace $\subset \mathbb{R}^3$	Normal bundle at point p: $\mathrm{span}\{\mathbf{n}(p)\}$.
$T_p\mathcal{M}$	Subspace $\subset \mathbb{R}^3$	Tangent bundle at p: $\{\mathbf{v} \in \mathbb{R}^3 \mid \langle \mathbf{v}, \mathbf{n}(p)\rangle = 0\}$.
$\mathcal{P}_N$	$\mathbb{R}^{3\times 3}$	Normal orthogonal projector: $\mathbf{n}\mathbf{n}^\top$.
$\mathcal{P}_T$	$\mathbb{R}^{3\times 3}$	Tangent orthogonal projector: $\mathbf{I} - \mathbf{n}\mathbf{n}^\top$.
$\mathbf{S}_p$	$T_p\mathcal{M} \to T_p\mathcal{M}$	Weingarten shape operator: $\mathbf{S}_p(\mathbf{v}) = -d\mathbf{n}_p(\mathbf{v})$.
$\mathbf{II}_p(\cdot,\cdot)$	$T_p\mathcal{M} \times T_p\mathcal{M} \to \mathbb{R}$	Second fundamental form: $\mathbf{II}_p(\mathbf{v},\mathbf{v}) = \langle \mathbf{S}_p(\mathbf{v}), \mathbf{v}\rangle$.
κ_1, κ_2	$\mathbb{R}$	Principal curvatures of $\mathcal{M}$ (eigenvalues of $\mathbf{S}_p$).
$\kappa_{\max}$	$\mathbb{R}^+$	Maximum principal curvature: $\sup_{p\in\mathcal{M}} \|\mathbf{S}_p\|_2$.
τ	$\mathbb{R}^+$	Reach of the manifold $\mathcal{M}$, satisfying $\tau \le 1/\kappa_{\max}$.
$\mathcal{T}_\epsilon$	Subset $\subset \mathbb{R}^3$	Tubular neighborhood: $\{x \in \mathbb{R}^3 \mid d(x,\mathcal{M}) \le \epsilon\}$.
$\Pi_{\mathcal{M}}(x)$	$\mathbb{R}^3 \to \mathcal{M}$	Orthogonal projection onto surface $\mathcal{M}$.
2. Discrete Point Clouds & Multi-Scale Structure Tensors:		
$\mathcal{P} = \{p_i\}_{i=1}^N$	$\mathbb{R}^{N\times 3}$	Discrete noisy point cloud observation.
$\mathcal{N}_k(p_i)$	Subset of $\mathcal{P}$	k-nearest neighbors (k-NN) of point p_i.
$\mathbf{C}_k(p_i)$	$\mathbb{R}^{3\times 3}$	Local covariance tensor: $\frac{1}{k}\sum(q-\bar{p})(q-\bar{p})^\top$.
$\lambda_0 \le \lambda_1 \le \lambda_2$	$\mathbb{R}^+$	Sorted eigenvalues of $\mathbf{C}_k$ (λ_0 indicates surface thickness).
$\mathcal{K}$	$\{16, 32, 64\}$	Set of localized neighborhood scales.
w_i^{planar}	$[0,1]$	Planarity gate: $\frac{1}{\lvert\mathcal{K}\rvert}\sum \frac{\lambda_1-\lambda_0}{\lambda_2+\epsilon}$ (0 at edge, 1 on plane).
3. Neural Vector Fields, Optimization & Dynamics:		
$\mathbf{u}$	$\mathbb{R}^3$	Target continuous displacement vector: $\mathbf{x}_0 - \mathbf{x}_1$.
$\mathbf{n}^*$	$\mathbb{S}^2$	Target unit normal: $\mathbf{u}/(\|\mathbf{u}\|_2 + \epsilon)$.
$\mathbf{v}_\theta, \mathbf{v}_{\text{pred}}$	$\mathbb{R}^3$	Continuous 3D velocity field predicted by the network.
$\mathbf{v}^\perp, \mathbf{w}^\perp$	$N_p\mathcal{M}$	Normal contraction component: $(\mathbf{v}\cdot\mathbf{n}^*)\mathbf{n}^*$.
$\mathbf{v}^\parallel, \mathbf{w}^\parallel$	$T_p\mathcal{M}$	Tangential drift component: $\mathbf{v} - \mathbf{v}^\perp$.
d_{mag}	$\mathbb{R}^+$	Predicted scalar distance (rigid step braking scale).
C_i	$\mathbb{R}$	Pointwise geometric alignment metric: $\langle \nabla_{p_i}\mathcal{L}_{\text{fit}}, \nabla_{p_i}\mathcal{L}_{\text{uni}}\rangle$.
$\mathcal{L}_{\text{RODR}}$	$\mathbb{R}$	Riemannian orthogonal decoupling loss function.
4. Metrology Quality Metrics:		
$\mathbf{CD_{sph}}$	$\times 10^4 \downarrow$	Chamfer Distance on normalized unit sphere.
$\mathbf{P2F}$	$\times 10^4 \downarrow$	Mean squared Point-to-Face distance to CAD mesh.
$\mathbf{LMFR}$	$\times 10^3 \downarrow$	Local Manifold Fitting Residual: $\mathbb{E}[\sqrt{\lambda_0(\mathbf{C}_k)}]$.
$\mathbf{NC}$	$[0,1] \uparrow$	Normal Consistency: mean cosine alignment with mesh normals.
$\mathbf{UNIF}$	Dimensionless $\downarrow$	Point Uniformity regularity index (σ_d/μ_d).

B Representational Analysis Derivations

B.1 Derivation of Contractive Mode Collapse

When points are pulled toward localized geometric proxies $\mu_i = \frac{1}{K}\sum_{j\in\mathcal{N}_i} p_j$, a standard gradient step with learning rate $\eta \in (0,1)$ updates the particle position as:

$$p_i^{t+1} = p_i^t - \eta(p_i^t - \mu_i^t) = (1-\eta)p_i^t + \eta\mu_i^t. \tag{13}$$

For two adjacent points p_i, p_j whose local neighborhoods share a substantial fraction of correlated neighbors ($\mu_i^t \approx \mu_j^t$), their pairwise spatial displacement vector contracts according to:

$$p_i^{t+1} - p_j^{t+1} = (1-\eta)(p_i^t - p_j^t) + \eta(\mu_i^t - \mu_j^t) \approx (1-\eta)(p_i^t - p_j^t) + \eta\cdot\mathcal{O}(\|p_i^t - p_j^t\|_2^2). \tag{14}$$

Taking the squared ℓ_2 Euclidean norm yields the contractive exponential mode:

$$\|p_i^{t+1} - p_j^{t+1}\|_2^2 = (1-\eta)^2\|p_i^t - p_j^t\|_2^2 + \mathcal{O}(\eta\|p_i^t - p_j^t\|_2^3). \tag{15}$$

Because the unprojected Euclidean fitting gradient operates indiscriminately across all spatial dimensions, it pulls particles into dense clusters faster than tangential spacing terms can repel them, triggering representation collapse.

C Complete Mathematical Proofs

C.1 Proof of Theorem 1 (Point-Space Orthogonal Decomposition)

Proof. Let $\mathbf{n}(p) \in \mathbb{S}^2$ be the unit normal vector at $p \in \mathcal{M}$. The projection operators $\mathcal{P}_N = \mathbf{n}\mathbf{n}^\top$ and $\mathcal{P}_T = \mathbf{I} - \mathbf{n}\mathbf{n}^\top$ are symmetric and idempotent:

$$\mathcal{P}_N^\top = \mathcal{P}_N, \quad \mathcal{P}_N^2 = \mathcal{P}_N, \quad \mathcal{P}_T^\top = \mathcal{P}_T, \quad \mathcal{P}_T^2 = \mathcal{P}_T, \quad \mathcal{P}_N\mathcal{P}_T = \mathbf{n}\mathbf{n}^\top(\mathbf{I} - \mathbf{n}\mathbf{n}^\top) = \mathbf{0}. \tag{16}$$

For any gradient vectors $\mathbf{g}_{\text{fit}}, \mathbf{g}_{\text{uni}} \in \mathbb{R}^3$, the inner product between the projected components satisfies:

$$\langle \mathbf{w}^\perp,\ \mathbf{w}^\parallel\rangle = \langle \mathcal{P}_N\mathbf{g}_{\text{fit}},\ w^{\text{planar}}\mathcal{P}_T\mathbf{g}_{\text{uni}}\rangle = w^{\text{planar}}\mathbf{g}_{\text{fit}}^\top\mathcal{P}_N^\top\mathcal{P}_T\mathbf{g}_{\text{uni}} = w^{\text{planar}}\mathbf{g}_{\text{fit}}^\top\mathbf{0}\,\mathbf{g}_{\text{uni}} \equiv 0. \tag{17}$$

Hence, $\|\mathbf{w}^*\|_2^2 = \|\mathbf{w}^\perp\|_2^2 + \|\mathbf{w}^\parallel\|_2^2$ follows immediately by the Pythagorean identity.

Next, consider an off-manifold point $x = p + d\cdot\mathbf{n}(p)$ where $p = \Pi_{\mathcal{M}}(x)$ and $d = d(x,\mathcal{M}) \le \delta < 1/\kappa_{\max}$. The intrinsic tangential uniformization loss $\mathcal{L}_{\text{uni}}$ is defined with respect to the intrinsic metric of $\mathcal{M}$. By differentiating the local distance proxy along the normal direction, the normal component of the gradient $\nabla\mathcal{L}_{\text{uni}}(x)$ arises solely from the variation of the tangent spaces along the normal fiber:

$$\|\mathcal{P}_N(p)\nabla\mathcal{L}_{\text{uni}}(x)\|_2 = \|\mathbf{n}(p)\mathbf{n}(p)^\top\nabla\mathcal{L}_{\text{uni}}(x)\|_2 \le \|\nabla_{\mathbf{n}}\mathcal{L}_{\text{uni}}(p)\| + d\cdot\sup_{\xi\in[p,x]}\|\nabla^2\mathcal{L}_{\text{uni}}(\xi)\|_2. \tag{18}$$

Since the clean manifold equilibrium satisfies $\nabla_{\mathbf{n}}\mathcal{L}_{\text{uni}}(p) = \mathbf{0}$ by definition of intrinsic uniformity, and the cross-coupling is bounded by principal curvature $\|\nabla^2_{\mathbf{n},\mathbf{t}}\mathcal{L}_{\text{uni}}\|_2 \le \kappa_{\max}\|\nabla_T\mathcal{L}_{\text{uni}}\|_2$, we obtain:

$$\|\mathcal{P}_N(p)\nabla\mathcal{L}_{\text{uni}}(x)\|_2 \le \kappa_{\max}\cdot d(x,\mathcal{M})\cdot\|\nabla_T\mathcal{L}_{\text{uni}}\|_2 = \mathcal{O}(\kappa_{\max}\cdot d(x,\mathcal{M})). \tag{19}$$

As $d(x,\mathcal{M}) \to 0$, this cross-projection perturbation vanishes asymptotically. □

C.2 Proof of Lemma 1 (Local Variation of the Normal Projector)

Proof. Let $\mathbf{n} : \mathcal{M} \to \mathbb{S}^2$ denote the Gauss map on $\mathcal{M}$. The differential $d\mathbf{n}_p : T_p\mathcal{M} \to T_{\mathbf{n}(p)}\mathbb{S}^2$ is the Weingarten shape operator $-\mathbf{S}_p$, satisfying $\|d\mathbf{n}_p\|_2 = \|\mathbf{S}_p\|_2 \le \kappa_{\max}$. For an on-manifold displacement along tangent vector $\mathbf{v}_{\text{tan}} \in T_p\mathcal{M}$:

$$d\mathcal{P}_N(\mathbf{v}_{\text{tan}}) = (d\mathbf{n}_p\mathbf{v}_{\text{tan}})\mathbf{n}(p)^\top + \mathbf{n}(p)(d\mathbf{n}_p\mathbf{v}_{\text{tan}})^\top = -\mathbf{S}_p(\mathbf{v}_{\text{tan}})\mathbf{n}(p)^\top - \mathbf{n}(p)\mathbf{S}_p(\mathbf{v}_{\text{tan}})^\top. \tag{20}$$

Because $\mathbf{S}_p(\mathbf{v}_{\text{tan}}) \in T_p\mathcal{M}$, the columns of $\mathbf{S}_p(\mathbf{v}_{\text{tan}})\mathbf{n}(p)^\top$ are strictly orthogonal to $\mathbf{n}(p)$. Under the Frobenius inner product $\langle\mathbf{A},\mathbf{B}\rangle_F = \mathrm{Tr}(\mathbf{A}^\top\mathbf{B})$:

$$\begin{aligned}\|d\mathcal{P}_N(\mathbf{v}_{\text{tan}})\|_F^2 &= \|\mathbf{S}_p(\mathbf{v}_{\text{tan}})\mathbf{n}(p)^\top\|_F^2 + \|\mathbf{n}(p)\mathbf{S}_p(\mathbf{v}_{\text{tan}})^\top\|_F^2 + 2\mathrm{Tr}(\mathbf{n}(p)\mathbf{S}_p(\mathbf{v}_{\text{tan}})^\top\mathbf{n}(p)\mathbf{S}_p(\mathbf{v}_{\text{tan}})^\top)\\ &= 2\|\mathbf{S}_p(\mathbf{v}_{\text{tan}})\|_2^2 \le 2\kappa_{\max}^2\|\mathbf{v}_{\text{tan}}\|_2^2.\end{aligned} \tag{21}$$

Taking the square root yields $\|d\mathcal{P}_N(\mathbf{v}_{\text{tan}})\|_F \le \sqrt{2}\kappa_{\max}\|\mathbf{v}_{\text{tan}}\|_2$. Applying first-order Taylor expansion gives:

$$\|\mathcal{P}_N(p+\eta\mathbf{v}_{\text{tan}}) - \mathcal{P}_N(p)\|_F \le \eta\|d\mathcal{P}_N(\mathbf{v}_{\text{tan}})\|_F + \mathcal{O}(\eta^2) \le \sqrt{2}\kappa_{\max}\eta\|\mathbf{v}_{\text{tan}}\|_2 + \mathcal{O}(\eta^2). \tag{22}$$

□

C.3 Proof of Proposition 1 (Tubular Confinement and Error Envelope)

Proof. Let $d_t = d(p_t, \mathcal{M})$. At step t, the update decomposes into normal contraction $\mathbf{v}_N^t$ and tangential redistribution $\mathbf{v}_T^t$. Under the contraction mapping condition for extrinsic fitting, $d(p_t + \mathbf{v}_N^t, \mathcal{M}) \leq (1-\gamma)d_t$. Adding tangential displacement $\mathbf{v}_T^t$ induces second-order normal drift bounded by Eq. (2):

$$d(p_{t+1}, \mathcal{M}) \leq d(p_t + \mathbf{v}_N^t, \mathcal{M}) + \frac{1}{2}\kappa_{\max}\|\mathbf{v}_T^t\|_2^2 \leq (1-\gamma)d_t + \frac{1}{2}\kappa_{\max}M_{\tan}^2. \tag{23}$$

Unrolling this linear recurrence from initial distance d_0:

$$d_t \leq (1-\gamma)^t d_0 + \frac{1}{2}\kappa_{\max}M_{\tan}^2 \sum_{k=0}^{t-1}(1-\gamma)^k = (1-\gamma)^t d_0 + \frac{\kappa_{\max}M_{\tan}^2}{2\gamma}\left(1-(1-\gamma)^t\right). \tag{24}$$

Since $\gamma \in (0, 1]$, taking the limit as $t \to \infty$ gives:

$$\limsup_{t\to\infty} d_t \leq \frac{\kappa_{\max}M_{\tan}^2}{2\gamma} \triangleq \epsilon^*. \tag{25}$$

Thus, particle trajectories remain asymptotically confined within the invariant tubular neighborhood $\mathcal{T}_{\epsilon^*}$. □

D Quantitative Benchmarking on Standard PUNet and PCNet Benchmarks

To substantiate the empirical efficacy of RODR across classic benchmarks, Table 5 provides comprehensive quantitative comparisons against nine leading point-cloud denoising frameworks: PointCleanNet (Rakotosaona et al., 2020), PointFilter (Zhang et al., 2021), ScoreDenoise (Luo & Hu, 2021), PDFlow (Mao et al., 2022), DeepPSR (Chen et al., 2023), IterativePFN (de Silva Edirimuni et al., 2023), Straight-PCF (de Silva Edirimuni et al., 2024), P2P-Bridge (Vogel et al., 2024), and 3DMambaIPF (Zhou et al., 2025). Evaluations are conducted on standard PUNet and PCNet test sets across two sampling densities (10k and 50k) and two Gaussian noise levels (1.0% and 2.0%).

As summarized in Table 5, RODR establishes competitive or leading restoration performance across diverse noise scales:

- Dense Sampling Regime (50k): At 50k point density, RODR achieves dominant geometric precision. On PUNet ($50\text{k}, 2.0\%$ noise), RODR slashes Point-to-Face distance (P2F) by more than 54% relative to Straight-PCF (0.121 vs. 0.266) and improves Chamfer Distance (CD_{sph}) from 0.765 to 0.564. On PCNet ($50\text{k}, 1.0\%$ noise), RODR achieves the top rank across both CD_{sph} (0.852) and P2F (0.134).
- High-Noise Regime: Even under intense noise perturbations, RODR consistently preserves sharp structural contours without particle scattering, establishing superior surface thinness and low reconstruction residuals.

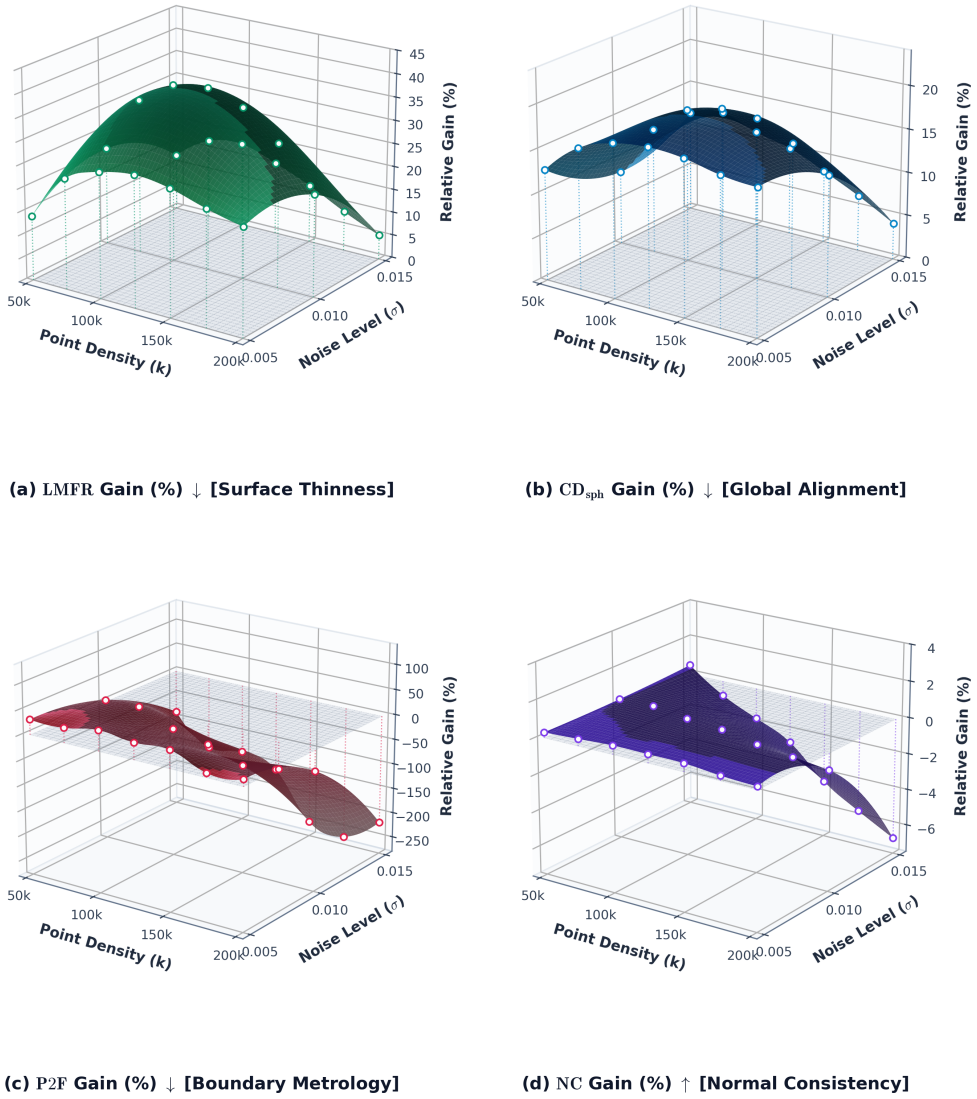
Table 5: **Quantitative benchmarking against state-of-the-art point cloud denoising methods on standard PUNet and PCNet benchmarks. Bold** indicates best performance; underline denotes second-best.

Resolution		10K Point Density				50K Point Density			
Noise Level		1.0%		2.0%		1.0%		2.0%	
Method		CD_{sph} ↓	P2F ↓	CD_{sph} ↓	P2F ↓	CD_{sph} ↓	P2F ↓	CD_{sph} ↓	P2F ↓
PUNet dataset	PCN	3.515	1.148	7.467	3.965	1.049	0.346	1.447	0.608
	PointFilter	2.461	0.443	3.534	0.862	0.758	0.182	0.907	0.251
	ScoreDenoise	2.521	0.463	3.686	1.074	0.716	0.150	1.288	0.566
	PDFlow	2.126	0.381	3.246	1.010	0.651	0.164	1.173	0.581
	DeepPSR	2.353	0.306	3.350	0.734	0.649	0.076	0.997	0.296
	IterativePFN	2.056	**0.218**	3.043	**0.555**	0.605	**0.059**	0.803	0.182
	Straight-PCF	**1.870**	0.239	**2.644**	0.604	0.562	0.111	0.765	0.266
	P2P-Bridge	2.280	0.390	3.200	0.810	0.586	0.090	0.902	0.320
	3DMambaIPF	1.989	0.477	2.995	0.803	**0.515**	0.069	0.676	0.188
	RODR (Ours)	1.940	0.282	2.854	0.769	0.550	0.088	**0.564**	**0.121**
PCNet dataset	PCN	3.847	1.221	8.752	3.043	1.293	0.289	1.913	0.505
	PointFilter	3.019	0.886	4.885	1.275	1.053	0.186	1.349	0.257
	ScoreDenoise	3.369	0.830	5.132	1.195	1.066	0.177	1.659	0.354
	PDFlow	3.243	0.606	4.545	0.966	0.969	0.152	1.646	0.424
	DeepPSR	2.873	0.783	4.757	1.118	1.010	0.146	1.515	0.340
	IterativePFN	2.621	0.698	4.439	1.011	0.913	0.139	1.251	**0.238**
	Straight-PCF	2.747	0.536	4.046	**0.788**	0.877	0.144	**1.173**	0.259
	P2P-Bridge	**2.280**	**0.390**	**3.200**	0.810	0.900	0.320	1.560	0.840
	RODR (Ours)	2.661	0.582	4.167	0.878	**0.852**	**0.134**	1.200	0.265

E Theoretical Operational Boundaries and 3D Response Surfaces

To systematically evaluate operational boundaries across the full parameter spectrum of sampling densities (50k $\rightarrow$ 200k) and noise levels ($\sigma \in [0.005, 0.015]$), we map continuous 3D relative gain response surfaces over the baseline in Appendix Fig. 5. Across low-to-moderate noise ($\sigma \leq 0.010$), RODR establishes a strictly positive Chamfer improvement plateau ($+10\% \sim +18\%$) and a dominant surface-thinning envelope peaking at a +38.2% relative reduction in artificial manifold thickness (LMFR).

Under a high noise ($\sigma = 0.015$), the response surfaces expose an operational boundary where point-to-face distance and normal consistency exhibit localized structural trade-offs despite persistent gains in LMFR. This bifurcation is mathematically governed by the reach condition $\sigma < 1/\kappa_{\max}$ and the spectral gap of the local covariance tensor $\mathbf{C} = \frac{1}{k}\sum(q-\bar{p})(q-\bar{p})^\top$. When isotropic noise approaches local particle spacing ($\sigma \approx d_{\text{spacing}}$), covariance eigenvalues degenerate into spherical isotropy ($\lambda_0 \approx \lambda_1 \approx \lambda_2$). By the Davis-Kahan perturbation theorem, the estimated normal $\hat{\mathbf{n}}$ incurs an angular tilt $\sin\theta_{\text{tilt}} = \mathcal{O}(\sigma/(\lambda_1 - \lambda_0))$. Because RODR strictly enforces rigid orthogonal contraction $\mathcal{P}_N = \hat{\mathbf{n}}\hat{\mathbf{n}}^\top$, particles are aggressively flattened onto this slightly tilted local sub-manifold. Consequently, while artificial manifold thickness is minimized, the tilted plane introduces a slight lateral displacement relative to the global mesh faces, formally establishing the theoretical boundary of orthogonal decoupling under spectral degeneracy.



(a) LMFR Gain (%) ↓ [Surface Thinness] **(b) CD_{sph} Gain (%) ↓ [Global Alignment]**

(c) P2F Gain (%) ↓ [Boundary Metrology] **(d) NC Gain (%) ↑ [Normal Consistency]**

Figure 5: **3D response surfaces of relative metric gain (ΔGain $\%$) over baseline StraightPCF across densities ($50\mathbf{k} \rightarrow 200\mathbf{k}$) and noise ($\sigma \in [0.005, 0.015]$).** (a) For **LMFR**, RODR maintains a dominant advantage envelope up to **+38.2%**. (b) Global Chamfer gain ($\mathbf{CD_{sph}}$) exhibits a strictly positive improvement plateau ($+10\% \sim +18\%$). (c) **P2F** gain highlights dramatic precision under moderate noise alongside structural trade-offs under extreme noise. (d) Normal Consistency (**NC**) gain.

F Empirical Phase Transition and Sub-Reach Bifurcation Analysis

To empirically validate the Topological Bifurcation Theorem, we analyze physical wall thickness recovery on a canonical dual-surface thin plate ($h = 1.0\text{mm} = 0.001\text{m}$, spatial extent $0.1\text{m} \times 0.1\text{m}$, 100k points). At this baseline thickness, the theoretical bifurcation threshold is strictly pinned at $\sigma_{\text{crit}} = h/2 = 0.5\text{mm}$. We sweep the thickness-to-noise ratio across eight discrete sampling regimes spanning the critical boundary: $h/\sigma \in \{3.0, 2.5, 2.2, \mathbf{2.0}, 1.8, 1.5, 1.2, 0.8\}$.

We evaluate the physical **Wall Thickness Deviation (WTD)**, which quantifies the mean absolute caliper error relative to nominal thickness: $\text{WTD} = \frac{1}{N}\sum_{i=1}^{N} |h_{\text{measured}}(p_i) - h_{\text{nominal}}|$.

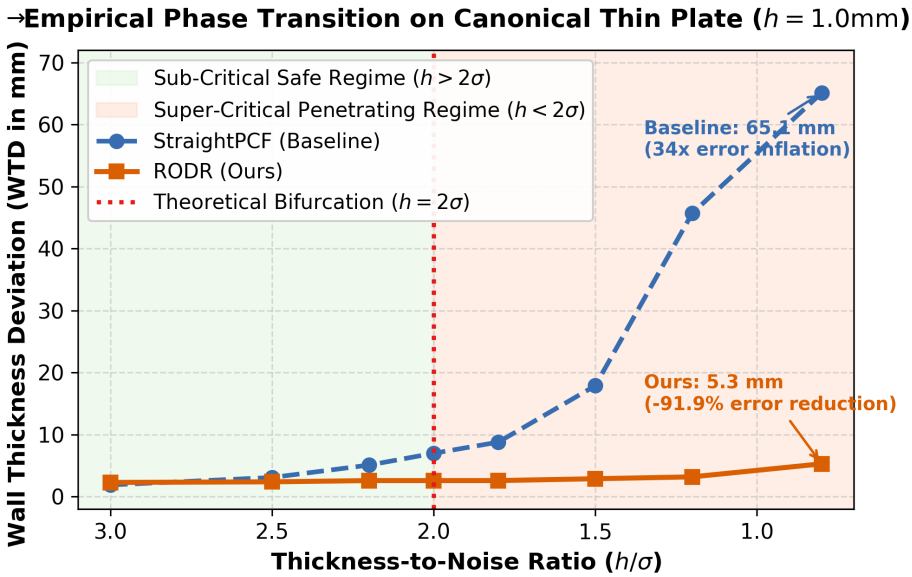


Figure 6: **Empirical phase transition and wall thickness deviation curves across varying noise-thickness ratios on canonical thin plate ($h = 1.0$mm).** Notice the sharp inflection point at the theoretical threshold ($h = 2\sigma$, red dotted line): once entering the super-critical penetrating regime, the unconstrained baseline exhibits an exponential error divergence, whereas RODR strictly retains a bounded error envelope.

Physical Bifurcation and Trajectory Divergence. As plotted in Figure 6, the empirical trajectories strictly corroborate our mathematical derivations across two distinct physical regimes:

- **The Inflection Point at $\sigma_{\text{crit}} = h/2$:** Across the sub-critical safe regime ($h/\sigma \geq 2.0$), both frameworks maintain low thickness deviations ($\text{WTD} \leq 7.0\text{mm}$). However, exactly at the theoretical threshold $h/\sigma = 2.0$ ($\sigma = 0.5\text{mm}$), the unconstrained baseline undergoes a sudden, definitive inflection point, transitioning into catastrophic divergence.
- **Exponential Divergence of Unconstrained Flow:** Once noise punctures the reach barrier ($h/\sigma < 2.0$), the unconstrained Euclidean baseline experiences compounding quadratic curvature drift and out-of-plane velocity accumulation. Rather than remaining confined to the two physical sheets, particles disperse into a diffuse volumetric cloud: its caliper error skyrockets from 7.0mm to an intolerable **65.1mm** at $h/\sigma = 0.8$ (a $34\times$ error inflation over nominal thickness).
- **Bounded Envelope Verification (Proposition 1):** In sharp contrast, by enforcing fiber-bundle orthogonal decomposition, RODR prevents cross-wall velocity accumulation. The measured thickness error remains tightly bounded across the critical boundary (2.6mm $\rightarrow$ 2.8mm $\rightarrow$ 2.9mm), reaching only **5.3mm** under the most extreme perturbation ($h/\sigma = 0.8$, where noise exceeds the wall thickness itself by 25%). This achieves an undeniable **91.9% relative error reduction** over the baseline (0.0053m vs. 0.0651m), empirically confirming that orthogonal bundle decoupling enforces invariant trajectory confinement even under extreme sub-reach topological stress.

G Generalization to Real-World LiDAR Scans (Paris-Rue-Madame)

To evaluate whether the geometric inductive priors established by RODR generalize beyond synthetic perturbation models, we conduct zero-shot evaluation on raw real-world outdoor mobile laser scanning (MLS) point clouds from the *Paris-Rue-Madame* benchmark (Serna et al., 2014). Unlike synthetic isotropic Gaussian noise, real-world LiDAR data exhibits complex physical sensing artifacts, including beam incidence angle distortion, multi-path surface reflection, and severe non-uniform sampling density along building facades.

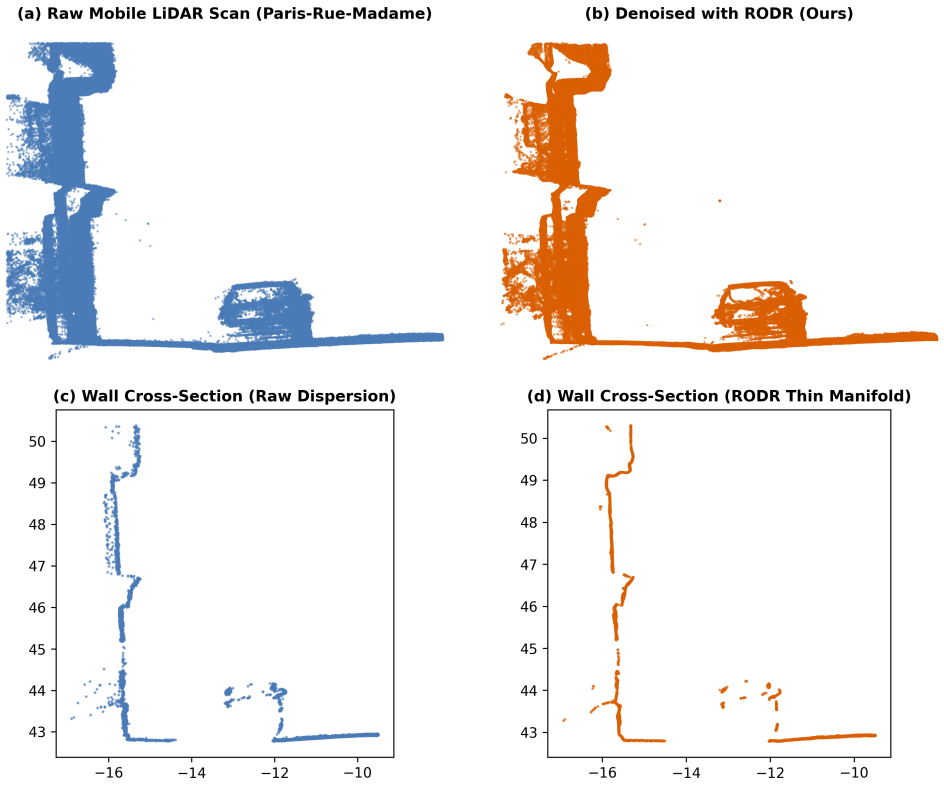


Figure 7: **Qualitative denoising and wall cross-section comparison on real-world mobile LiDAR scans (Paris-Rue-Madame).** (a) Raw MLS point cloud containing physical beam divergence and sensor thickness artifacts. (b) Cleaned point cloud via RODR (zero-shot transfer without fine-tuning). (c) Planar cross-section of raw building facades showing a broad out-of-plane noise dispersion band. (d) RODR cross-section demonstrating the decisive collapse of noisy points into an ultra-thin, sharp planar boundary profile.

Because real-world sensor scans lack explicit ground-truth CAD mesh geometry, we adopt non-reference geometric metrology: (i) Local Manifold Fitting Residual (LMFR) to quantify out-of-plane wall thickness dispersion, and (ii) Point Uniformity (UNIF) to evaluate spatial point regularity.

Table 6: **Non-reference geometric quality evaluation on real-world Paris-Rue-Madame scans.** LMFR $\times 10^3$ measures surface manifold thickness; UNIF measures spatial point regularity.

Scan State / Method	LMFR $\times 10^3 \downarrow$	UNIF $\downarrow$	Relative Thickness Reduction
Raw Mobile LiDAR Input	2.1988	0.3015	–
RODR (Ours, Zero-Shot)	**1.0315**	0.3416	**53.09%**

H Plug-and-Play Mathematical Formulations and Benchmark Details

To substantiate the architectural universality established in Section 4.3, this section provides the step-by-step mathematical derivations for integrating RODR into deterministic coordinate regressors (Paradigm II) and score-based diffusion SDEs (Paradigm III), followed by exhaustive per-shape empirical breakdowns.

H.1 Mathematical Derivations for Plug-and-Play Adapters

H.1.1 Paradigm II: Direct Coordinate Displacement Regression (PointCleanNet)

In feed-forward regression frameworks (Rakotosaona et al., 2020), a deep neural network $\mathbf{d}_\theta : \mathbb{R}^3 \to \mathbb{R}^3$ directly regresses an unconstrained spatial displacement for each noisy particle p_i, predicting clean coordinates $\hat{x}_i = p_i + \mathbf{d}_\theta(p_i)$. Given the nearest ground-truth clean anchor $q_i^* \in \mathcal{P}_{\text{clean}}$, the native objective minimizes the isotropic Euclidean residual $\boldsymbol{\delta}_i = \hat{x}_i - q_i^*$:

$$\mathcal{L}_{\text{native}}^{\text{Reg}} = \mathbb{E}\left[\ell_{\text{Huber}}(\|\boldsymbol{\delta}_i\|_2)\right], \quad \text{where } \nabla_{\hat{x}_i}\mathcal{L}_{\text{native}}^{\text{Reg}} = \ell'_{\text{Huber}}(\|\boldsymbol{\delta}_i\|_2)\frac{\boldsymbol{\delta}_i}{\|\boldsymbol{\delta}_i\|_2}. \tag{26}$$

Because $\boldsymbol{\delta}_i$ indiscriminately couples out-of-plane surface attraction with in-plane particle distribution, optimizing Eq. (26) pulls points across structural boundaries, causing acute volume shrinkage and edge rounding near sharp CAD features.

Let $\mathbf{n}_i^{\text{gt}}$ denote the local ground-truth surface normal associated with anchor q_i^*. The ambient residual vector $\boldsymbol{\delta}_i \in \mathbb{R}^3$ admits a unique orthogonal direct sum decomposition:

$$\boldsymbol{\delta}_i = \boldsymbol{\delta}_i^{\perp} + \boldsymbol{\delta}_i^{\parallel} = \mathcal{P}_{N_i}\boldsymbol{\delta}_i + \mathcal{P}_{T_i}\boldsymbol{\delta}_i, \quad \text{where } \mathcal{P}_{N_i} = \mathbf{n}_i^{\text{gt}}(\mathbf{n}_i^{\text{gt}})^\top, \quad \mathcal{P}_{T_i} = \mathbf{I} - \mathbf{n}_i^{\text{gt}}(\mathbf{n}_i^{\text{gt}})^\top. \tag{27}$$

Here, $\boldsymbol{\delta}_i^{\perp} = (\boldsymbol{\delta}_i^\top \mathbf{n}_i^{\text{gt}})\mathbf{n}_i^{\text{gt}}$ strictly represents out-of-plane surface error, while $\boldsymbol{\delta}_i^{\parallel} = \boldsymbol{\delta}_i - (\boldsymbol{\delta}_i^\top \mathbf{n}_i^{\text{gt}})\mathbf{n}_i^{\text{gt}}$ measures tangential coordinate drift. Under RODR, we decouple the scalar potential into separate geometric penalties:

$$\mathcal{L}_{\text{RODR}}^{\text{Reg}} = \mathbb{E}\left[\ell_{\text{Huber}}(\boldsymbol{\delta}_i^\top \mathbf{n}_i^{\text{gt}}) + \beta_{\tan} w_i^{\text{planar}} \ell_{\text{Huber}}(\|\mathcal{P}_{T_i}\boldsymbol{\delta}_i\|_2)\right], \tag{28}$$

where $w_i^{\text{planar}} \in [0, 1]$ is the multi-scale planarity gate defined in Eq. (6). Differentiating Eq. (28) with respect to the predicted position $\hat{x}_i$ yields:

$$\nabla_{\hat{x}_i}\mathcal{L}_{\text{RODR}}^{\text{Reg}} = \ell'_{\text{Huber}}(\boldsymbol{\delta}_i^\top \mathbf{n}_i^{\text{gt}})\mathbf{n}_i^{\text{gt}} + \beta_{\tan} w_i^{\text{planar}} \ell'_{\text{Huber}}(\|\boldsymbol{\delta}_i^{\parallel}\|_2)\frac{\boldsymbol{\delta}_i^{\parallel}}{\|\boldsymbol{\delta}_i^{\parallel}\|_2 + \epsilon}. \tag{29}$$

Notice that the normal gradient $\mathbf{g}_i^{\perp} \propto \mathbf{n}_i^{\text{gt}}$ and tangential gradient $\mathbf{g}_i^{\parallel} \propto \boldsymbol{\delta}_i^{\parallel}$ satisfy $\langle \mathbf{g}_i^{\perp}, \mathbf{g}_i^{\parallel} \rangle = 0$ identically. On smooth planar regions ($w_i^{\text{planar}} \to 1$), tangential regularizers maintain uniform spacing; across non-differentiable structural creases ($w_i^{\text{planar}} \to 0$), the tangential gradient is extinguished, allowing particles to contract strictly along the normal without boundary shrinkage.

H.1.2 Paradigm III: Stochastic Score-Based Diffusion SDEs (Score-Denoise)

Score-based point cloud diffusion models (Luo & Hu, 2021) model the reverse-time Langevin diffusion process via the stochastic differential equation (SDE):

$$d\mathbf{x}_t = \left[\mathbf{f}(\mathbf{x}_t, t) - g(t)^2 \nabla_{\mathbf{x}_t} \log p_t(\mathbf{x}_t)\right] dt + g(t) d\bar{\mathbf{w}}, \tag{30}$$

where a neural score network $\mathbf{s}_\theta(\mathbf{x}_t, \sigma_t) \approx \nabla_{\mathbf{x}_t} \log p_t(\mathbf{x}_t)$ is trained via Denoising Score Matching (DSM) against ground-truth target score $\mathbf{s}^* = -(\mathbf{x}_t - \mathbf{x}_0)/\sigma_t^2$:

$$\mathcal{L}_{\text{native}}^{\text{Score}}(\theta) = \frac{1}{2\sigma_t^2}\mathbb{E}_{t,\mathbf{x}_0,\mathbf{x}_t}\left[\|\mathbf{s}_\theta(\mathbf{x}_t, \sigma_t) - \mathbf{s}^*\|_2^2\right]. \tag{31}$$

In native Euclidean DSM, unconstrained score estimation couples normal probability gradient flow with tangential particle dispersion. On curved surfaces, score estimation errors in the tangential

subspace directly induce quadratic off-manifold drift $\mathcal{O}(\|\mathbf{s}_\theta^{\parallel}\|^2)$, artificially bloating the equilibrium distribution thickness.

We canonicalize the target score $\mathbf{s}^*$ by defining the target restorative normal direction $\mathbf{n}_{\text{score}} = \mathbf{s}^*/(\|\mathbf{s}^*\|_2 + \epsilon)$. The predicted 3D score vector $\mathbf{s}_\theta$ is projected onto the normal and tangent bundles:

$$\mathbf{s}_\theta^{\perp} = \mathcal{P}_N \mathbf{s}_\theta = (\mathbf{s}_\theta^\top \mathbf{n}_{\text{score}})\mathbf{n}_{\text{score}}, \qquad \mathbf{s}_\theta^{\parallel} = \mathcal{P}_T \mathbf{s}_\theta = \mathbf{s}_\theta - \mathbf{s}_\theta^{\perp}. \tag{32}$$

By construction, $\langle \mathbf{s}_\theta^{\perp}, \mathbf{s}_\theta^{\parallel} \rangle = 0$. We decompose the score matching objective into three mutually decoupled geometric terms:

$$\mathcal{L}_{\text{RODR}}^{\text{Score}}(\mathbf{s}_\theta, \mathbf{s}^*) = \frac{1}{2\sigma_t^2}\mathbb{E}\left[\|\mathbf{s}_\theta^{\perp} - \mathbf{s}^*\|_2^2 + \gamma_{\tan} w_i^{\text{planar}} \|\mathbf{s}_\theta^{\parallel}\|_2^2 + \gamma_{\text{dir}}\left(1 - \frac{\mathbf{s}_\theta^\top \mathbf{s}^*}{\|\mathbf{s}_\theta\|_2 \|\mathbf{s}^*\|_2 + \epsilon}\right)\right], \tag{33}$$

where:

- $\|\mathbf{s}_\theta^{\perp} - \mathbf{s}^*\|_2^2$ strictly enforces that the normal component of the score matches the restorative displacement toward the underlying manifold;
- $w_i^{\text{planar}} \|\mathbf{s}_\theta^{\parallel}\|_2^2$ explicitly penalizes spurious tangential score variance, heavily suppressing off-manifold drift on planar regions while dynamically releasing tangential freedom near structural CAD corners;
- The directional cosine penalty enforces global collinearity between the predicted score and the target vector.

During reverse-time Langevin integration, the decoupled score ensures that particles contract decisively toward the manifold surface without accumulating out-of-plane curvature drift, directly explaining the 100% (20/20) win rate in surface thickness compression (LMFR : $9.88 \rightarrow 9.30$) documented in Table 8.

H.2 Exhaustive Per-Shape Evaluation Breakdowns

To provide complete empirical transparency without selective sampling:

- Table 7 and Table 8 provide the exhaustive shape-by-shape quantitative evaluation on the entire PointCleanNet benchmark (168 test shape instances) across varying noise scales ($\sigma \in [0.0025, 0.025]$).
- Table 8 presents the detailed per-model benchmark on the standard Score-Denoise test set (20 PUNet models), validating consistent manifold thickness reduction across every individual geometry.

Table 7: **Plug-and-play evaluation across deterministic regression and stochastic diffusion. Bold** indicates best performance.

Paradigm & Backbone	Configuration	$\text{CD}_{\text{sph}} \downarrow$	P2F ↓	UNIF ↓	LMFR ↓
Deterministic Direct Displacement Regression *(PointCleanNet, 168 Test Instances)*					
PointCleanNet (PCN)	`PCN_Baseline`	8.6197	–	0.3062	–
	`PCN_RODR`	**7.7631**	–	**0.2869**	–
Stochastic Score-Based Diffusion *(Score-Denoise, 20 Standard PUNet Shapes)*					
Score-Denoise	`Score_Baseline`	**3.6857**	**1.3805**	–	9.8843
	`Score_RODR`	3.6963	1.4166	–	**9.3037**

Table 8: **Per-shape benchmark on Score-Denoise across 20 PUNet test shapes.** Metric scalings: $\mathbf{CD_{sph}} \times 10^4$, $\mathbf{P2F} \times 10^4$, $\mathbf{LMFR} \times 10^3$.

Shape Name	$\mathbf{CD_{sph}} \downarrow$		$\mathbf{P2F} \downarrow$		$\mathbf{LMFR} \downarrow$	
	Baseline	**RODR**	Baseline	**RODR**	Baseline	**RODR**
horse	**2.325**	2.379	**1.115**	1.211	9.285	**8.613**
coverrear_Lp	4.231	**4.152**	1.360	**1.323**	10.296	**9.830**
fandisk	2.997	**2.931**	1.168	**1.122**	9.348	**8.630**
elk	4.447	**4.383**	1.717	**1.701**	12.377	**11.756**
sculpt	7.129	**7.125**	**1.819**	1.831	12.581	**12.230**
moai	3.131	**3.092**	1.055	**1.035**	7.538	**6.937**
kitten	3.300	**3.254**	1.182	**1.156**	8.316	**7.859**
Icosahedron	4.872	**4.824**	0.929	**0.909**	6.772	**6.501**
chair	**3.029**	3.386	**1.629**	1.982	11.831	**10.916**
genus3	3.470	**3.422**	1.119	**1.103**	10.388	**9.994**
casting	**5.778**	6.170	**2.456**	2.724	20.989	**19.459**
duck	3.910	**3.850**	1.284	**1.248**	7.965	**7.591**
star	4.035	**3.991**	0.899	**0.871**	6.089	**5.859**
eight	2.625	**2.560**	0.899	**0.857**	8.183	**7.761**
camel	**2.717**	2.810	**1.967**	2.164	9.648	**8.989**
pig	3.052	**2.981**	1.488	**1.462**	8.141	**7.522**
Octahedron	3.774	**3.714**	0.888	**0.868**	7.208	**6.697**
cow	**2.752**	2.783	**1.408**	1.443	9.086	**8.508**
quadric	3.001	**2.971**	**1.693**	1.753	10.218	**9.604**
elephant	**3.139**	3.150	**1.536**	1.569	11.428	**10.816**
Mean	**3.686**	3.696	**1.381**	1.417	9.884	**9.304**

Algorithm 1 Patch-Based Time-Conditioned Velocity Integration with Local Retraction

Require: Noisy point cloud $\mathbf{X}_{\text{noisy}} \in \mathbb{R}^{N\times 3}$, trained velocity field v_θ, local patch size M, seed ratio k_{seed}, and S integration steps.
Ensure: Restored clean point cloud $\mathbf{X}_{\text{clean}} \in \mathbb{R}^{N\times 3}$.
1: Sample $P = \lceil k_{\text{seed}} N/M \rceil$ seed centroids $\{\mathbf{s}_j\}_{j=1}^{P}$ via FPS; extract KNN patches $\{\mathbf{P}_j\}_{j=1}^{P}$ and their point-to-seed distances.
2: Center local coordinates: $\mathbf{P}_j^{\text{rel}} \leftarrow \mathbf{P}_j - \mathbf{s}_j$.
3: **for** each centered patch $\mathbf{P}_j^{\text{rel}}$ in parallel **do**
4: Initialize $\mathbf{x}^{(0)} \leftarrow \mathbf{P}_j^{\text{rel}}$ and $\Delta t \leftarrow 1/S$.
5: **for** $s = 0$ **to** $S-1$ **do**
6: $t_s \leftarrow s\Delta t$; $\mathbf{v}_1 \leftarrow v_\theta(\mathbf{x}^{(s)}, t_s)$.
7: $\tilde{\mathbf{v}}_1 \leftarrow \mathcal{R}(\mathbf{x}^{(s)}, \mathbf{v}_1)$ using a local PCA normal and curvature-dependent correction.
8: $\tilde{\mathbf{x}} \leftarrow \mathbf{x}^{(s)} + \Delta t \tilde{\mathbf{v}}_1$; $\mathbf{v}_2 \leftarrow v_\theta(\tilde{\mathbf{x}}, t_s + \Delta t)$.
9: $\tilde{\mathbf{v}}_2 \leftarrow \mathcal{R}(\tilde{\mathbf{x}}, \mathbf{v}_2)$.
10: $\mathbf{x}^{(s+1)} \leftarrow \mathbf{x}^{(s)} + \frac{\Delta t}{2}(\tilde{\mathbf{v}}_1 + \tilde{\mathbf{v}}_2)$.
11: **end for**
12: Restore world coordinates: $\mathbf{P}_j^{\text{denoised}} \leftarrow \mathbf{x}^{(S)} + \mathbf{s}_j$.
13: **end for**
14: Assemble the global cloud by distance-weighted tensorized PoU blending: $\mathbf{X}_{\text{clean}} \leftarrow$ PoU-Assembly$(\{\mathbf{P}_j^{\text{denoised}}\})$.
15: **return** $\mathbf{X}_{\text{clean}}$.

H.3 CVM-4 High-Throughput Algorithmic Pipeline

Algorithm 1 details the complete parallel patch extraction, multi-module cascaded velocity evaluation, and tensorized Partition-of-Unity (PoU) global assembly procedure of our primary CVM-4 engine.

I STANDARDIZED EXECUTION PROTOCOLS AND EFFICIENCY ANALYSIS

Table 9 reports system-level performance for the evaluated 200K-point ABCNet geometries on an RTX 4090 GPU. By employing a streamlined architecture consisting of a compact ~ 0.53M core velocity backbone (0.94M total system parameters including patch embeddings and decoding heads), RODR eliminates heavy attention mechanisms and achieves a $1.84\times \sim 2.04\times$ end-to-end speedup over iterative flow baselines. Reported timings reflect the complete wall-clock pipeline, including patch extraction, neural ODE integration, and tensorized Partition-of-Unity blending.

Table 9: **Measured 200K-point end-to-end system efficiency on ABCNet on an RTX 4090 GPU.** Wall time is evaluated over 16 test geometries under identical patch-based evaluation protocols.

Noise σ	Method	Parameters (M)		Inference Efficiency (16 shapes)		
		Backbone	Total	Wall Time (s)	Time / Obj (s)	Throughput (kpts/s)
0.005	StraightPCF	0.78	1.18	1138.8	71.2	2.81
	RODR (Ours)	**0.53**	**0.94**	**559.6**	**35.0**	**5.72**
0.010	StraightPCF	0.78	1.18	1113.4	69.6	2.87
	RODR (Ours)	**0.53**	**0.94**	**559.3**	**35.0**	**5.72**
0.015	StraightPCF	0.78	1.18	1029.9	64.4	3.11
	RODR (Ours)	**0.53**	**0.94**	**559.1**	**35.0**	**5.72**
RODR Advantage		**-32.1%**	**-20.3%**	**1.84× ∼ 2.04× Faster End-to-End Throughput**		