Supplementary Material – Video to Events: Recycling Video Datasets for Event Cameras

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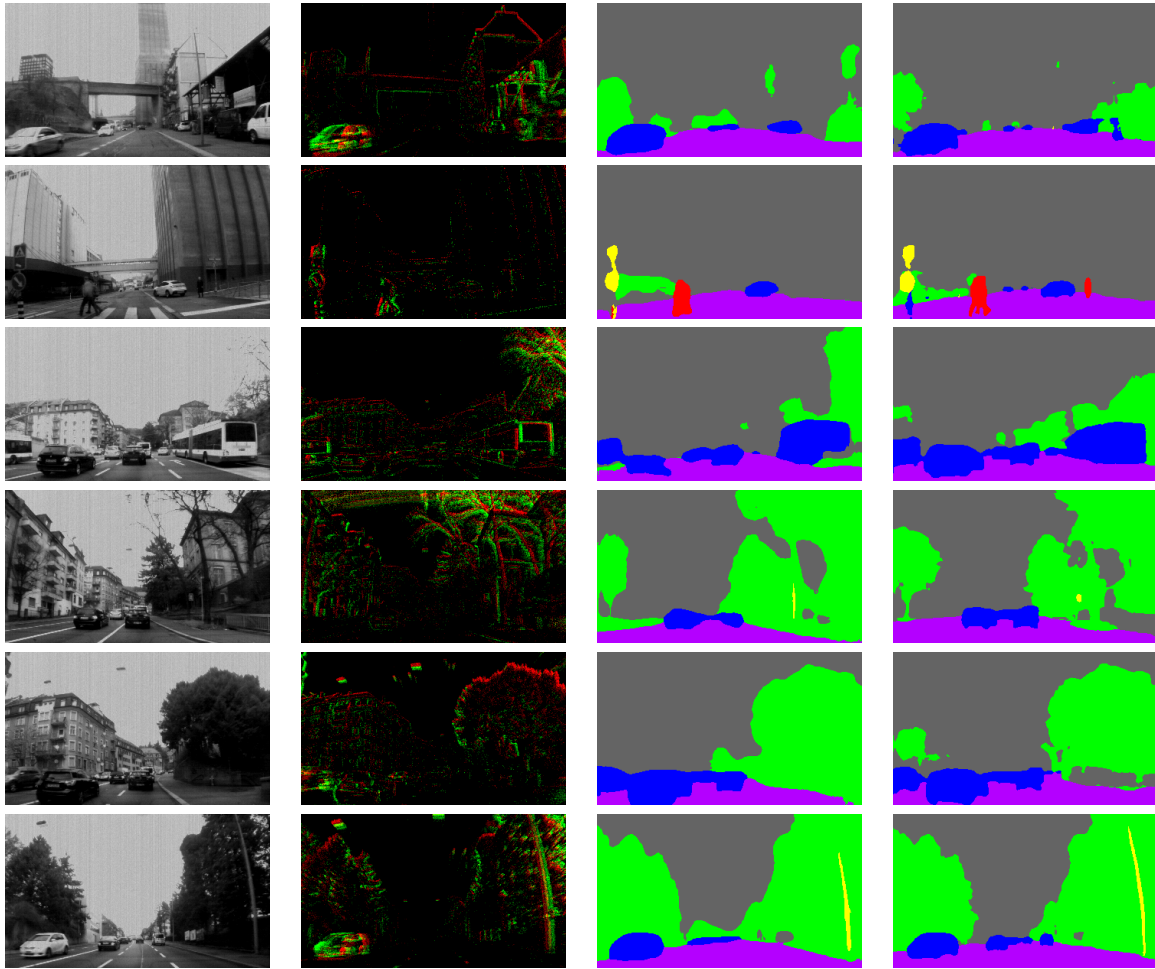
1. Appendix

In this section we provide additional qualitative results from our segmentation experiment in Sec. 4.2. Several examples from the test set can be viewed in Fig. 1. We used the network trained with the EST event representation and fine-tuned on real data. Fine-tuning was only performed for two epochs.

References

[1] Iñigo Alonso and Ana C Murillo. EV-SegNet: Semantic segmentation for event-based cameras. In *IEEE Conf. Comput. Vis. Pattern Recog. Workshops (CVPRW)*, 2019. 2

[2] Jonathan Binas, Daniel Neil, Shih-Chii Liu, and Tobi Delbruck. DDD17: End-to-end DAVIS driving dataset. In *ICML Workshop on Machine Learning for Autonomous Vehicles*, 2017. 2

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(a) DAVIS frame   (b) events   (c) prediction   (d) labels

Figure 1. A side-by-side view of event-based semantic segmentation predictions for the test set of the DAVIS Driving Dataset (DDD17) [2]. (a) DAVIS frame, (b) visualization of the events used to generate the predictions in (c) and (d) the ground truth labels generated from the frames in (a) [1]. The colors represent the following classes: violet: street; green: vegetation; red: person; blue: car; yellow: object; gray: background).