

# Supplementary Notes for Neuromorphic Optical Flow and Real-time Implementation with Event Cameras

Yannick Schneider<sup>1,2</sup>, Stanisław Woźniak<sup>1</sup>, Mathias Gehrig<sup>3</sup>, Jules Lecomte<sup>4</sup>, Axel von Arnim<sup>4</sup>,  
Luca Benini<sup>2,5</sup>, Davide Scaramuzza<sup>3</sup>, Angeliki Pantazi<sup>1</sup>

<sup>1</sup>IBM Research – Zurich <sup>2</sup>ETH Zurich <sup>3</sup>University of Zurich <sup>4</sup>fortiss GmbH <sup>5</sup>Università di Bologna

## 1. WAEE metric definition

The weighted average end point error (WAEE) combines the AEEs of the four sequences:

- outdoor\_day1 (od1)
- indoor\_flying1 (if1)
- indoor\_flying2 (if2)
- indoor\_flying3 (if3)

and is defined as:

$$\text{WAEE} = \left( \frac{\text{AEE}_{\text{od1}}}{w_{\text{od1}}} + \frac{\text{AEE}_{\text{if1}}}{w_{\text{if1}}} + \frac{\text{AEE}_{\text{if2}}}{w_{\text{if2}}} + \frac{\text{AEE}_{\text{if3}}}{w_{\text{if3}}} \right) / 4.$$

The weights  $w_{\text{od1}}$ ,  $w_{\text{if1}}$ ,  $w_{\text{if2}}$ ,  $w_{\text{if3}}$  are the sequence specific average AEEs of the spiking EV-FlowNet variants: LIF, ALIF, PLIF and XLIF for the modes  $dt = 1$  and  $dt = 4$  published in [1]:

$dt = 1 :$

$$\begin{aligned} w_{\text{od1}} &= (0.53 + 0.57 + 0.60 + 0.45) / 4.0 = 0.5375 \\ w_{\text{if1}} &= (0.71 + 1.00 + 0.75 + 0.73) / 4.0 = 0.7975 \\ w_{\text{if2}} &= (1.44 + 1.78 + 1.52 + 1.45) / 4.0 = 1.5475 \\ w_{\text{if3}} &= (1.16 + 1.55 + 1.23 + 1.17) / 4.0 = 1.2775 \end{aligned}$$

$dt = 4 :$

$$\begin{aligned} w_{\text{od1}} &= (2.02 + 2.13 + 2.24 + 1.67) / 4.0 = 2.0150 \\ w_{\text{if1}} &= (2.63 + 3.81 + 2.80 + 2.72) / 4.0 = 2.9900 \\ w_{\text{if2}} &= (4.93 + 6.40 + 5.21 + 4.93) / 4.0 = 5.3675 \\ w_{\text{if3}} &= (3.88 + 5.53 + 4.12 + 3.91) / 4.0 = 4.3600 \end{aligned}$$

(1)

## 2. Additional comparison

Table 1 includes an extended comparison with additional prior art non-spiking models. In particular, EV-FlowNet<sub>PM</sub> [3] was trained in comparable setting to ours, but used a photometric loss (PM). The results had been only reported for  $dt = 1$  mode. Furthermore, several prior art architectures were trained in a different setup using directly the MVSEC dataset, as opposed to our architectures that were trained on the UZH-FPV Drone Racing Dataset and evaluated on the MVSEC dataset. Results for models trained directly on MVSEC, delimited by dashed lines, include:

- EV-FlowNet<sub>PM-MVSEC</sub> [4], trained in a self-supervised manner with the photometric loss (PM),
- EV-FlowNet<sub>CM-MVSEC</sub> [5], trained in a self-supervised manner with a contrast maximisation loss (CM),
- Hybrid-EV-FlowNet<sub>MVSEC</sub> [2], trained in a self-supervised manner with the photometric loss.

Considering the extended comparison with non-spiking ANN prior art models, the EV-FlowNet<sub>CM-MVSEC</sub> [5] yields the best performance on all MVSEC sequences for  $dt = 1$  with regard to WAEE and percentage of outliers. Its WAEE of 0.67 is 8.2% lower than 0.73 of our sSNU-Timelens. In turn, the Hybrid-EV-FlowNet<sub>MVSEC</sub> [2] is outperformed by our sSNU-Timelens by 26.0% (0.73 vs. 0.92).

However, when evaluating in mode  $dt = 4$ , the Hybrid-EV-FlowNet<sub>MVSEC</sub> [2] yields the best overall performance with an WAEE of 0.68 compared to our sSNU-Timelens with 0.71 (+4.4%). The sSNU-Timelens shows on par performance in terms of WAEE with the EV-FlowNet<sub>CM-MVSEC</sub> [5] (also 0.71) in this mode.

In summary, the EV-FlowNet<sub>CM-MVSEC</sub> [5] and the Hybrid-EV-FlowNet<sub>MVSEC</sub> [2] perform best for MVSEC evaluations with  $dt = 1$  and  $dt = 4$ , respectively. Remarkably, our sSNU-Timelens is a runner-up in both cases, despite being trained without access to the examples from the MVSEC dataset.

	outdoor_day1		indoor_flying1		indoor_flying2		indoor_flying3		overall	
	AEE	%Out.	AEE	%Out.	AEE	%Out.	AEE	%Out.	WAEE	$\overline{\%Out.}$
dt = 1										
LIF-EV-FlowNet [1]	0.53	0.33	0.71	1.41	1.44	12.75	1.16	9.11	0.93	5.90
XLIF-EV-FlowNet [1]	0.45	<b>0.16</b>	0.73	<u>0.92</u>	1.45	12.18	1.17	8.35	0.90	5.40
LIF-FireNet [1]	0.57	0.40	0.98	2.48	1.77	16.40	1.50	12.81	1.15	8.02
PLIF-FireNet [1]	0.56	0.38	0.90	1.93	1.67	14.47	1.41	11.17	1.10	7.00
our SNN-Timelens	<u>0.44</u>	0.18	<u>0.70</u>	<b>0.79</b>	<u>1.30</u>	<u>9.41</u>	<u>1.05</u>	<u>6.00</u>	<u>0.84</u>	<u>4.10</u>
our SNUo-Timelens	<b>0.39</b>	<u>0.17</u>	<b>0.64</b>	0.96	<b>1.17</b>	<b>7.71</b>	<b>0.96</b>	<b>4.92</b>	<b>0.76</b>	<b>3.44</b>
EV-FlowNet <sub>PM</sub> [3]	0.92	5.4	0.79	1.2	1.40	10.9	1.18	7.4	1.13	6.23
EV-FlowNet [1]	0.47	0.25	<u>0.60</u>	<u>0.51</u>	<u>1.17</u>	<u>8.06</u>	<u>0.93</u>	5.64	0.78	<u>3.61</u>
RNN-EV-FlowNet [1]	0.56	1.09	0.62	0.97	1.20	8.82	<u>0.93</u>	<u>5.51</u>	0.83	4.10
our sSNU-Timelens	<u>0.36</u>	<u>0.10</u>	<b>0.58</b>	0.56	1.19	8.78	0.96	6.11	<u>0.73</u>	3.89
EV-FlowNet <sub>PM-MVSEC</sub> [4]	0.49	0.20	1.03	2.20	1.72	15.10	1.53	11.90	1.13	7.35
EV-FlowNet <sub>CM-MVSEC</sub> [5]	<b>0.32</b>	<b>0.00</b>	<b>0.58</b>	<b>0.00</b>	<b>1.02</b>	<b>4.00</b>	<b>0.87</b>	<b>3.00</b>	<b>0.67</b>	<b>1.75</b>
Hybrid-EV-FlowNet <sub>MVSEC</sub> [2]	0.49	-	0.84	-	1.28	-	1.11	-	0.92	-
dt = 4										
LIF-EV-FlowNet [1]	2.02	18.91	2.63	29.55	4.93	51.10	3.88	41.49	0.92	35.26
XLIF-EV-FlowNet [1]	1.67	12.69	2.72	31.69	4.93	51.36	3.91	42.52	0.89	34.57
LIF-FireNet [1]	2.12	21.00	3.72	48.27	6.27	64.16	5.23	58.43	1.17	47.97
PLIF-FireNet [1]	2.11	20.64	3.44	44.02	5.94	64.02	4.98	57.53	1.11	46.55
our SNN-Timelens	<u>1.65</u>	<u>11.03</u>	<u>2.61</u>	<u>29.40</u>	<u>4.50</u>	<u>50.87</u>	<u>3.58</u>	<u>40.22</u>	<u>0.84</u>	<u>32.88</u>
our SNUo-Timelens	<b>1.44</b>	<b>8.98</b>	<b>2.36</b>	<b>24.18</b>	<b>3.98</b>	<b>44.71</b>	<b>3.25</b>	<b>36.01</b>	<b>0.75</b>	<b>28.47</b>
EV-FlowNet [1]	1.69	12.50	2.16	<u>21.51</u>	3.90	<b>40.72</b>	<b>3.00</b>	<b>29.60</b>	0.74	<u>26.08</u>
RNN-EV-FlowNet [1]	1.91	16.39	2.23	22.10	4.01	41.74	<u>3.07</u>	<u>30.87</u>	0.78	27.78
our sSNU-Timelens	1.34	<u>7.99</u>	<b>2.15</b>	<b>20.92</b>	3.97	<u>41.31</u>	3.17	32.44	<u>0.71</u>	<b>25.67</b>
EV-FlowNet <sub>PM-MVSEC</sub> [4]	<u>1.23</u>	<b>7.30</b>	2.25	24.70	4.05	45.30	3.45	39.70	0.73	29.25
EV-FlowNet <sub>CM-MVSEC</sub> [5]	1.30	9.70	2.18	24.20	<u>3.85</u>	46.80	3.18	47.80	<u>0.71</u>	32.13
Hybrid-EV-FlowNet <sub>MVSEC</sub> [2]	<b>1.09</b>	-	2.24	-	<b>3.83</b>	-	3.18	-	<b>0.68</b>	-

Table 1. Extended evaluation on MVSEC: AEE (the lower, the better ↓), the percentage of outliers %Out.(↓) per sequence, and the overall WAEE(↓) as defined in Eq. 1 as well as the average percentage of outliers  $\overline{\%Out.}$ (↓). Best scores are in bold, while runner-ups are underlined. Horizontal lines delimit the spiking and the non-spiking models. Dashed line delimits not directly comparable prior art setups.

## References

- [1] Jesse Hagenars, Federico Paredes-Vallés, and Guido de Croon. Self-supervised learning of event-based optical flow with spiking neural networks. *Advances in Neural Information Processing Systems*, 34, 2021. 1, 2
- [2] Chankyu Lee, Adarsh Kosta, Alex Zhu, Kenneth Chaney, Kostas Daniilidis, and Kaushik Roy. *Spike-FlowNet: Event-Based Optical Flow Estimation with Energy-Efficient Hybrid Neural Networks*, pages 366–382. Oct 2020. 1, 2
- [3] F. Paredes-Vallés and Guido C.H.E. de Croon. Back to event basics: Self-supervised learning of image reconstruction for event cameras via photometric constancy. *2021 IEEE/CVF Conference on Computer Vision and Pattern Recognition (CVPR)*, pages 3445–3454, 2020. 1, 2
- [4] Alex Zhu, Liangzhe Yuan, Kenneth Chaney, and Kostas Daniilidis. EV-FlowNet: Self-supervised optical flow estimation for event-based cameras. In *Robotics: Science and Systems XIV. Robotics: Science and Systems Foundation*, Jun 2018. 1, 2
- [5] Alex Zihao Zhu, Liangzhe Yuan, Kenneth Chaney, and Kostas Daniilidis. Unsupervised event-based learning of optical flow, depth and egomotion. In *2019 IEEE/CVF Conference on Computer Vision and Pattern Recognition Workshops (CVPRW)*, pages 1694–1694, 2019. 1, 2