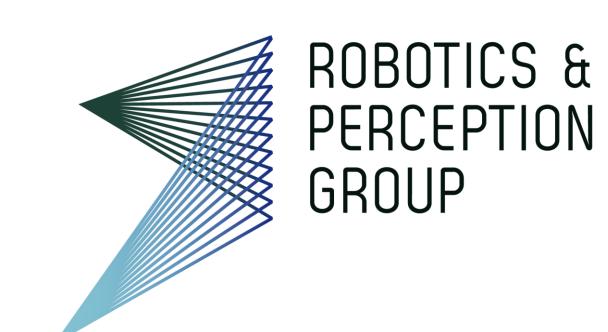


## Focus is All You Need: Loss Functions for Event-based Vision





Guillermo Gallego, Mathias Gehrig, Davide Scaramuzza

**Motivation:** Event cameras promise to revolutionize computer vision by unlocking challenging scenarios: HDR, high speed, low latency.

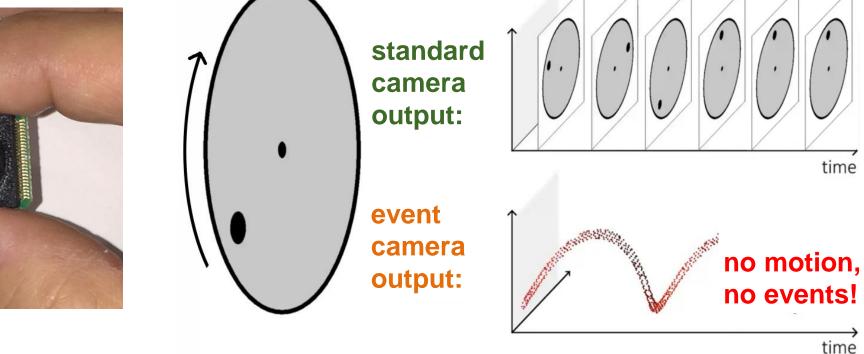
Goal: Develop and compare loss functions for event-based optimization problems (3D reconstruction, motion estimation, etc.) that can be used in unsupervised learning

### **Key Ideas:**

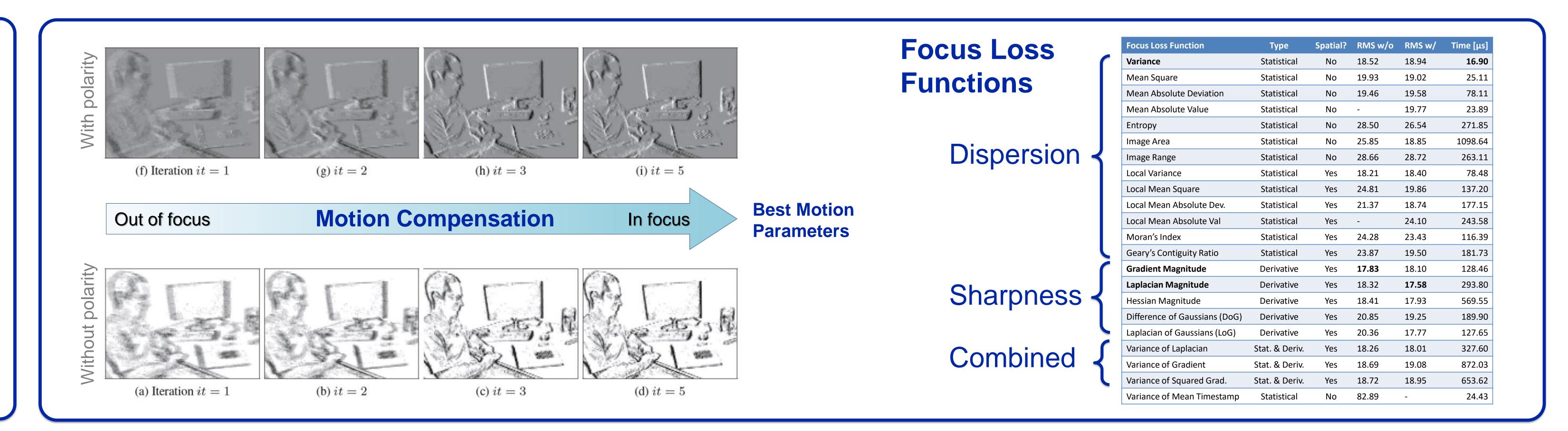
- Motion estimation by Focus Maximization.
- Connect event-based vision and shape-from-focus.
- Compare multiple (>20) objective functions.
- What functions are the best? Practical conclusions.
- Applications: depth and motion estimation, segmentation.

#### **Motion Compensation Framework** Input Events **Warped Events** Focus score $\mathbf{x}_k' = \mathbf{W}(\mathbf{x}_k, t_k; \boldsymbol{\theta})$ Warp events Measure even $H(\mathbf{x}; \boldsymbol{\theta}) = \sum_{k=1}^{N_e} b_k \delta(\mathbf{x} - \mathbf{x}_k')$ **Optimize motion parameters**

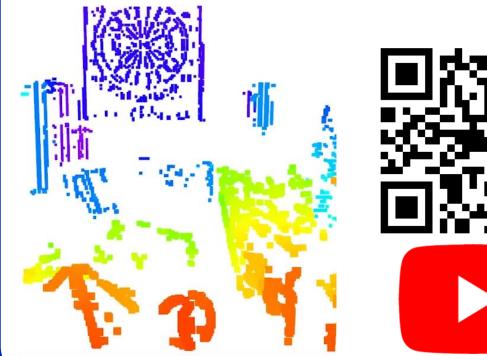
# What is an Event Camera?



- Only transmits brightness changes.
- Output is a stream of asynchronous events.
- Advantages: low latency, no motion blur, HDR.

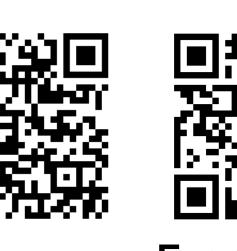


### Videos, survey paper and resources!









## **Event-based** Survey Research paper Sponsors FNSNF

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