

Supplementary Material — Learning to Estimate Two Dense Depths from LiDAR and Event Data^{*}

Vincent Brebion^[0000-0001-7429-0547], Julien Moreau^[0000-0001-5008-9232], and Franck Davoine^[0000-0002-8587-6997]

Heudiasyc (Heuristics and Diagnosis of Complex Systems) Laboratory, CNRS, Université de technologie de Compiègne (UTC), 60319 Compiègne Cedex, France
{vincent.brebion,julien.moreau,franck.davoine}@hds.utc.fr

1 Linear vs Log Scale

In this article, we use a linear scale for the event sensor in CARLA rather than the default logarithmic scale. We argue here that the logarithmic scale amplifies too much the creation of events in the dark areas of the image, as a very slight change in the intensity results in a large logarithmic intensity change, thus triggering an event. On the contrary, in the clearer areas, little to no events are produced, as a large intensity change is necessary to generate a logarithmic difference sufficient to trigger an event. An illustration of this phenomenon is given in Fig. 1 and Fig. 2.

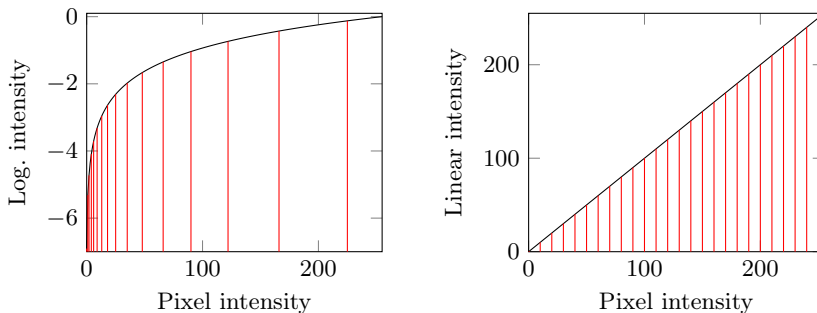
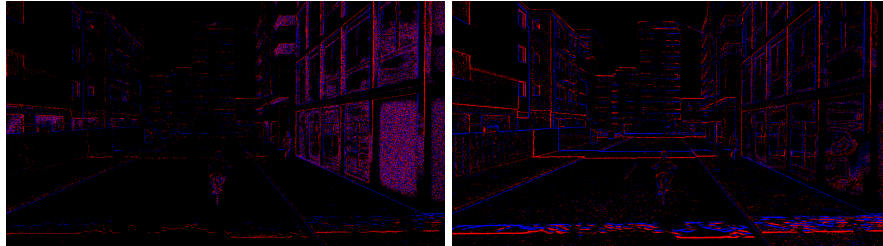


Fig. 1: Comparison of the triggering of events when the logarithmic and the linear scales are used. The logarithmic intensity in CARLA is computed as $\ln(I/255 + 0.001)$, where I is the pixel intensity. Each red vertical line denotes the triggering of an event, with thresholds set to 0.3 for the logarithmic scale, and 10 for the linear scale.

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(a) Generated RGB image



(b) Generated events with log. scale (c) Generated events with linear scale

Fig. 2: Visual comparison of the triggering of events when the logarithmic and the linear scales are used for a urban scene in CARLA. With the logarithmic scale, notice how the dark building on the right generates a high amount of events compared to the other buildings, and how details such as road markings or shadows are mostly lost. In comparison, with the linear scale, notice how the events are better distributed in the image.

2 Example Data from our SLED Dataset

We showcase in Fig. 3 some example data from our SLED dataset. In particular, we display here illustrations from two very different recordings: one on *Town01* during daytime, and a second one on *Town07* during nighttime.

3 Detailed Results on our SLED Dataset

As a complement to the summarized results shown in Table 2 of the main article on our SLED dataset, we provide here the full results for every recording on both maps of the testing set, *Town01* and *Town03*. These results are given in Table 1 and 2 respectively.



Fig. 3: Example data from the “Town01_04” (left) and “Town07_00” (right) sequences from our SLED dataset. Top to bottom: RGB image; depth image; events; projected LiDAR points; color scale.

4 Additional Dense Depths Results on our SLED Dataset

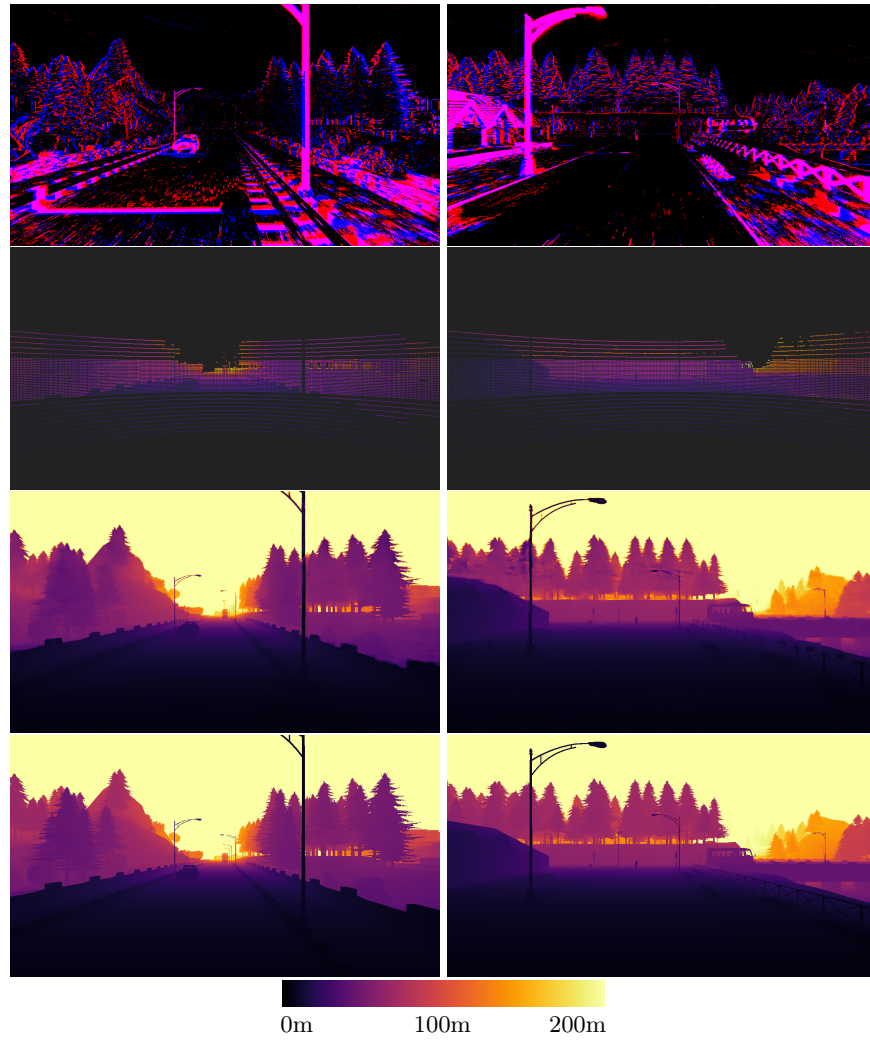


Fig. 4: Additional dense depths results on the SLED dataset.

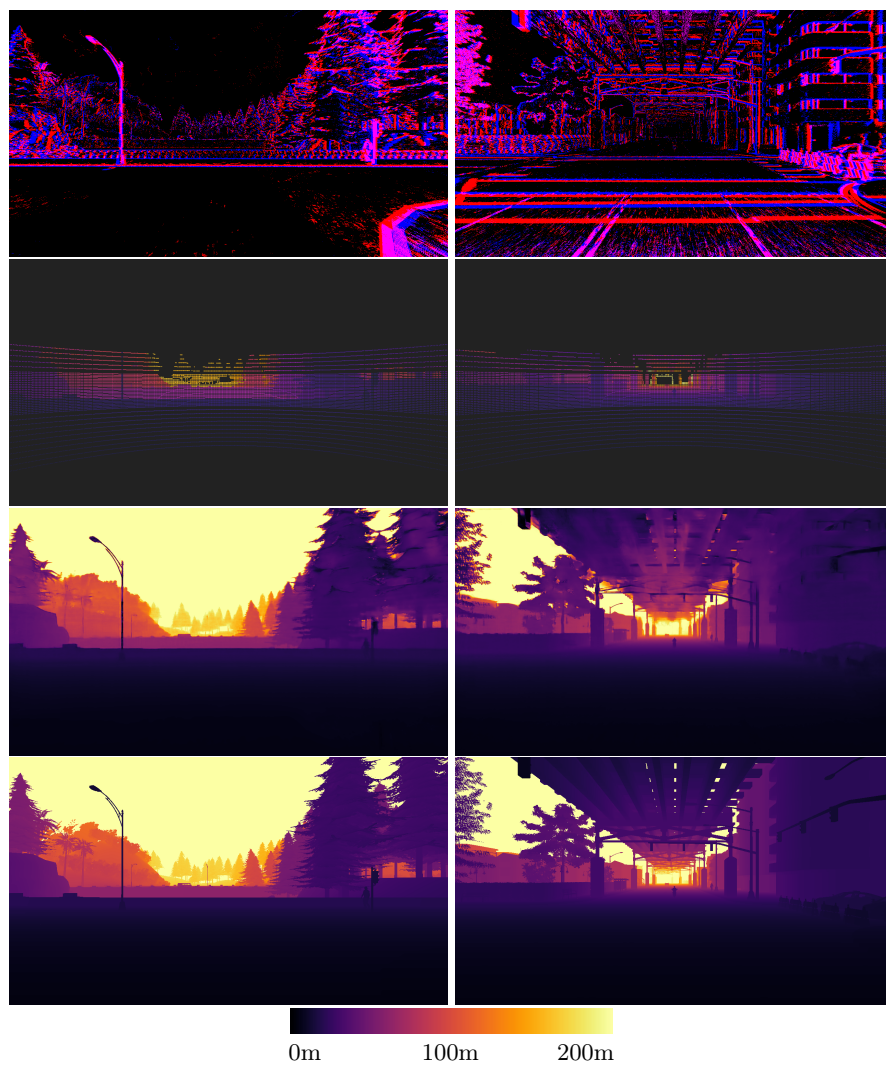


Fig. 5: Additional dense depths results on the SLED dataset.

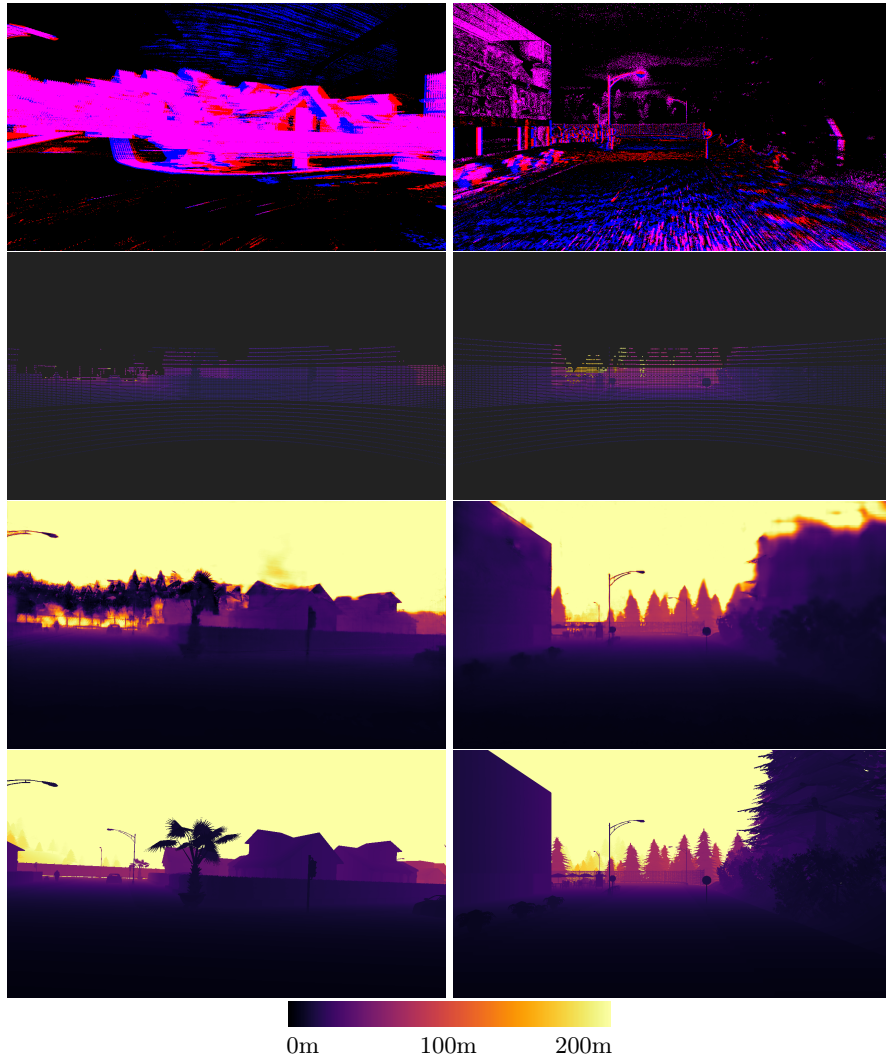


Fig. 6: Additional dense depths results on the SLED dataset. Illustrated here are two failure cases. Left: due to a sharp turn at high speed, accumulated events become too blurry, resulting in an incorrect prediction for distant objects. Right: night scene, where the trees on the right side are too dark to be seen even by the event camera, resulting in a partially blurry prediction.

5 Additional Dense Depths Results on the MVSEC Dataset

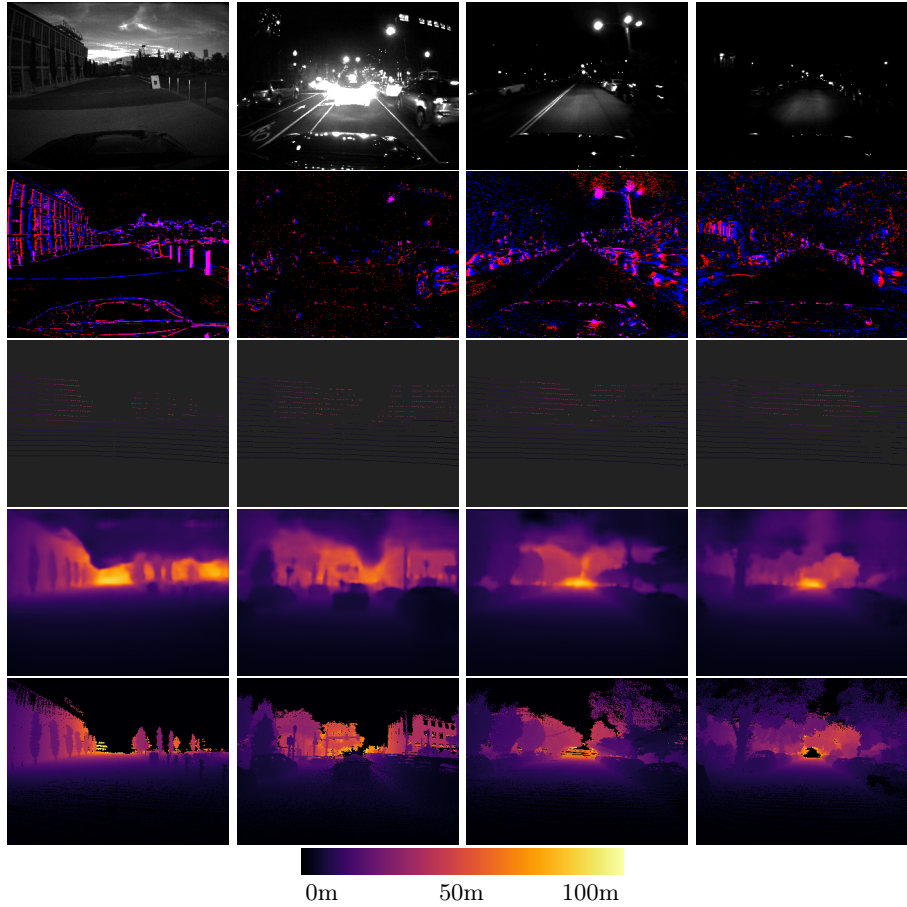


Fig. 7: Additional dense depths results on the MVSEC dataset. From left to right: “Outdoor day 1”, “Outdoor night 1”, “Outdoor night 2”, “Outdoor night 3”. From top to bottom: grayscale reference, events, LiDAR, prediction ($ALED_{S \rightarrow R}$), ground truth, color scale.

6 Thresholded Depth Change Maps Illustrations on our SLED Dataset

We present in Fig. 8 and 9 qualitative results for the thresholded depth change maps. These results visually corroborate the numerical analysis presented in the

main article, i.e., the overall accurate classification of the events. Some errors can still be seen, especially for the lower parts of the objects: as they are closer to the ground, the depth difference is less significant, and errors on the depth change map become therefore more critical.

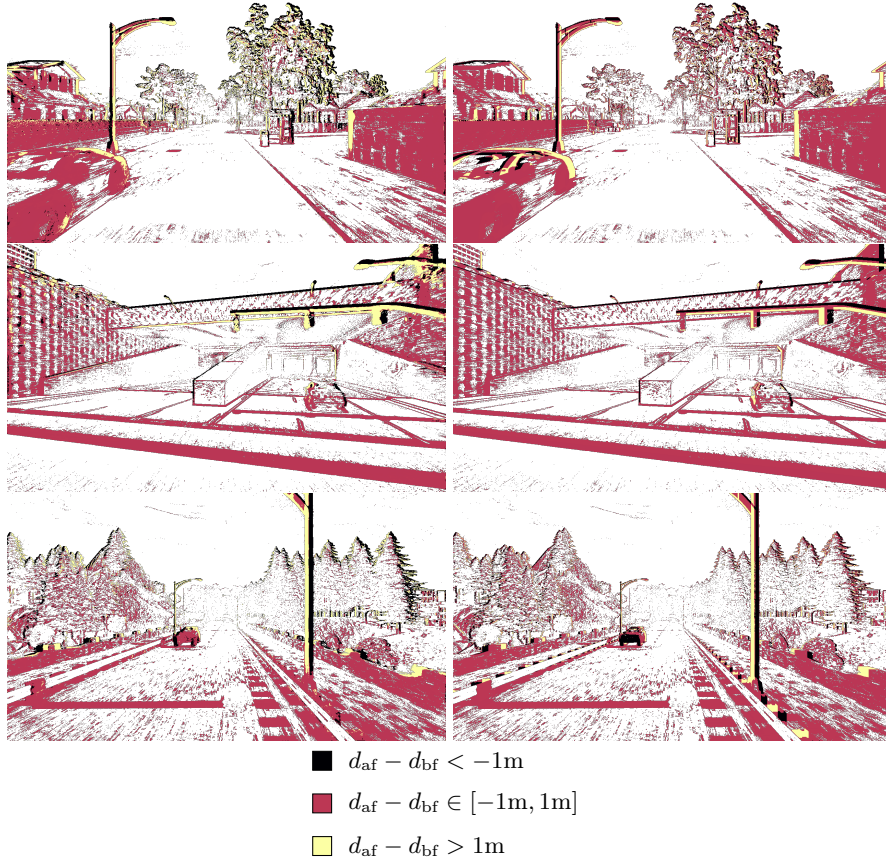


Fig. 8: Thresholded depth change map results, using the events as a mask. Left: prediction (ALED_S). Right: ground truth.

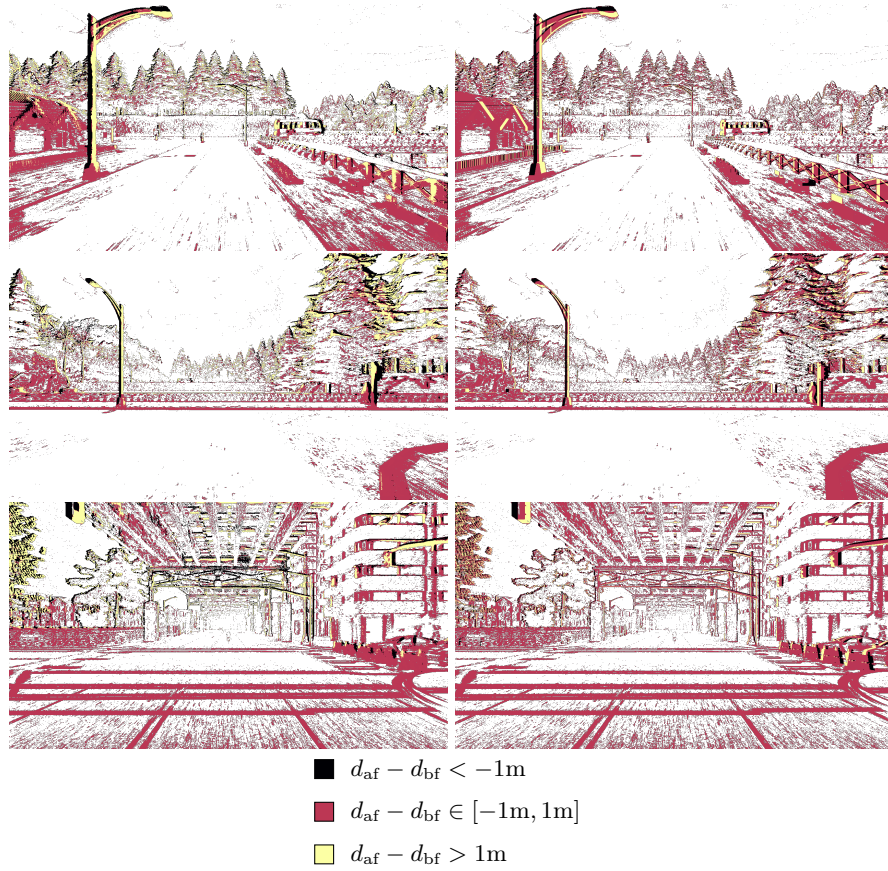


Fig. 9: Additional thresholded depth change map results, using the events as a mask. Left: prediction (ALED_S). Right: ground truth.