

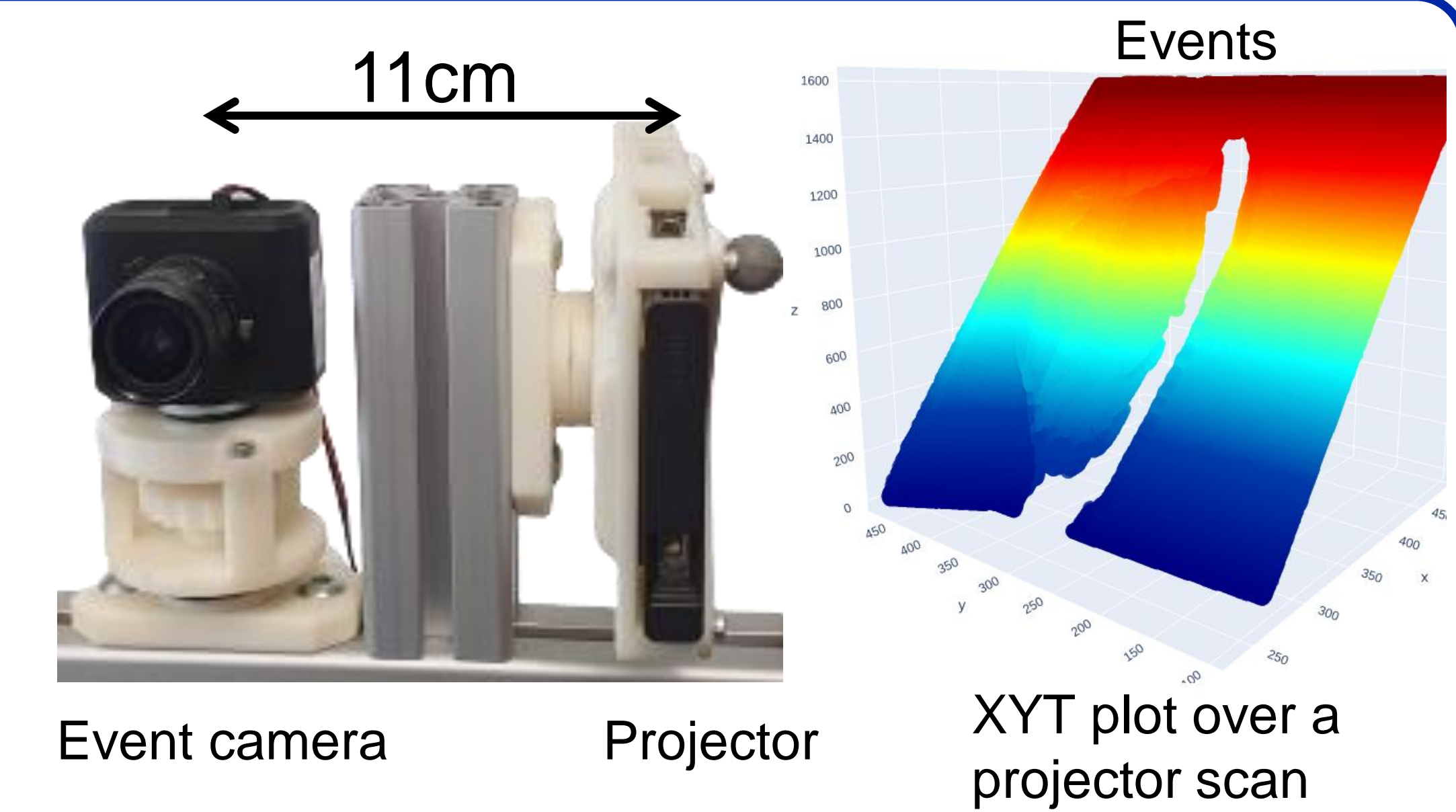


Motivation: Structured Light (SL) using standard cameras is not robust to motion blur and HDR. They suffer from accuracy versus speed trade-off.

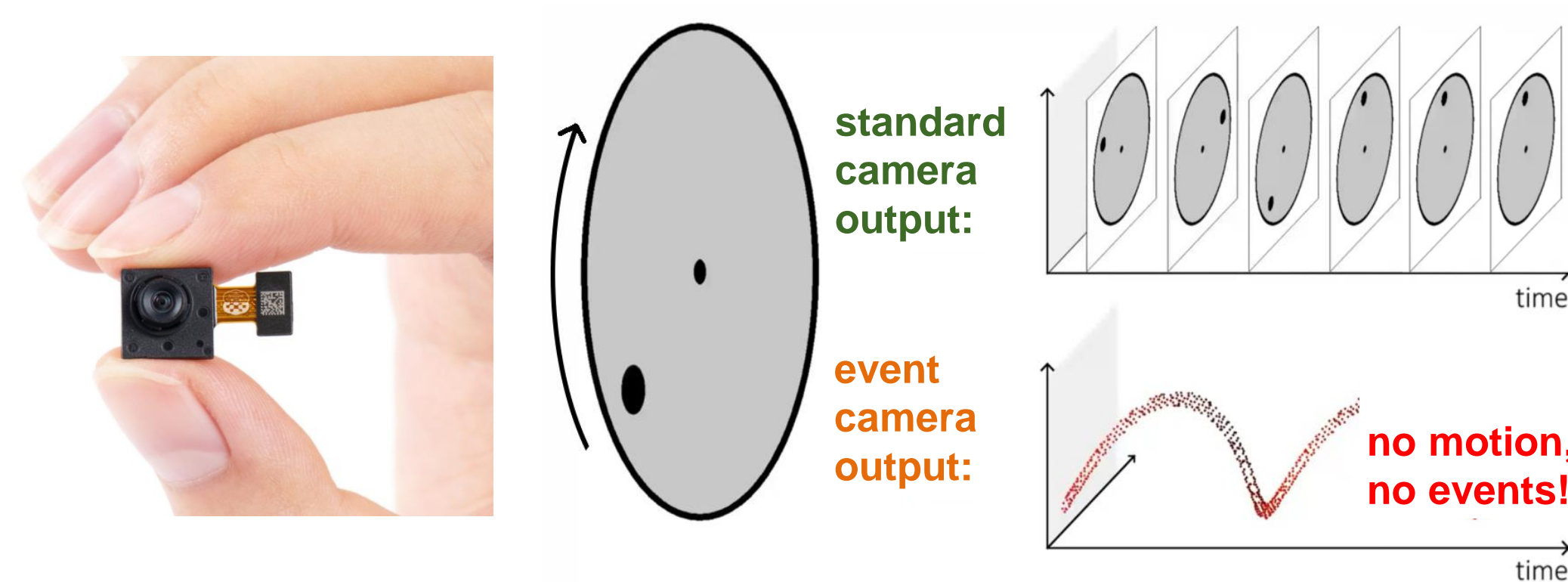
Goal: Novel structured light system using an event camera for accurate and high-speed depth sensing

Key Properties:

- Dense scene reconstruction with an event camera and laser point projector
- Model the projector as an inverse event camera
- Estimate the depth by minimizing spatio-temporal consistency
- **More accurate and robust to noise** in event timestamps than state-of-the-art
- Works in **high-speed and HDR scenes** where standard frame-based SL fails



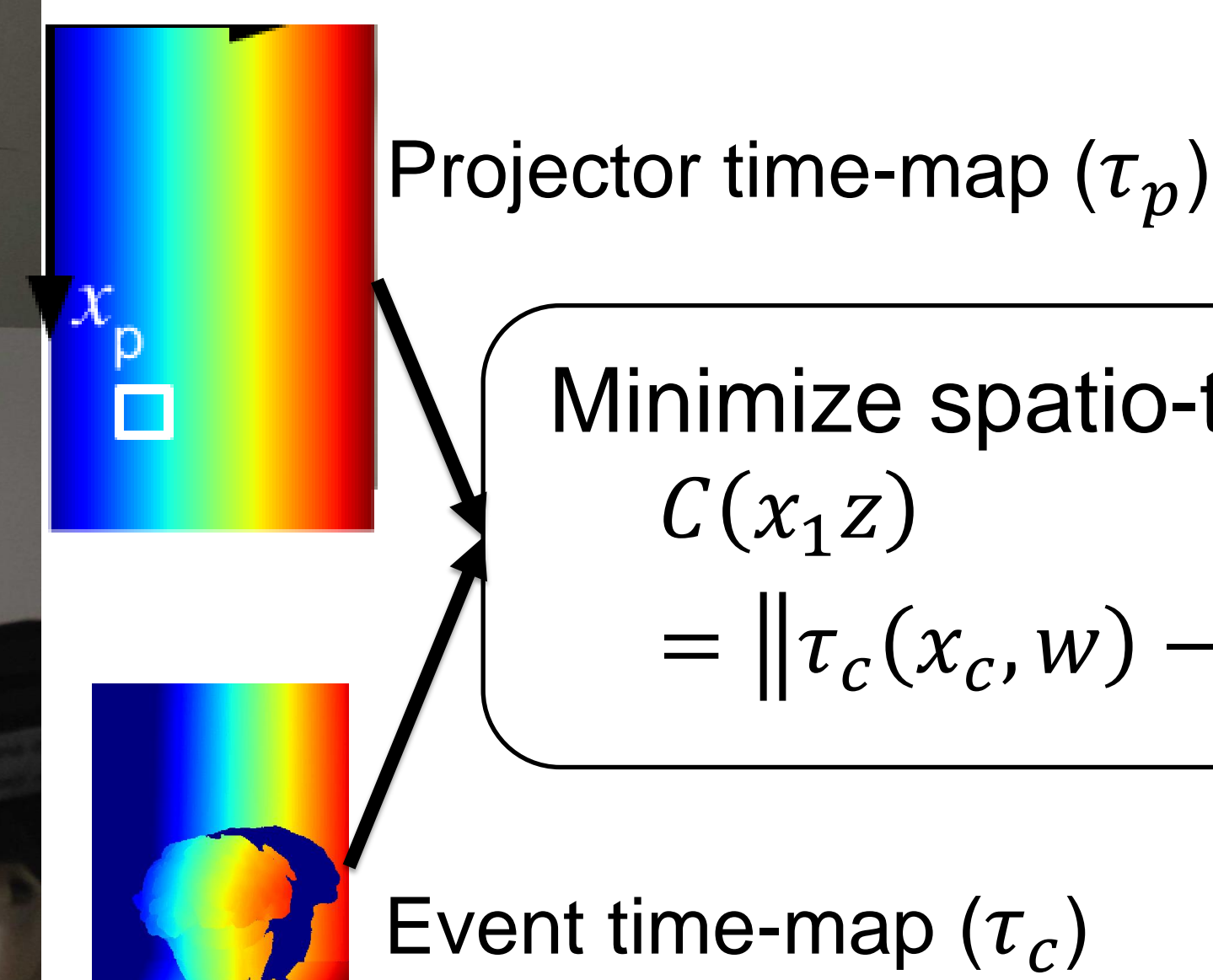
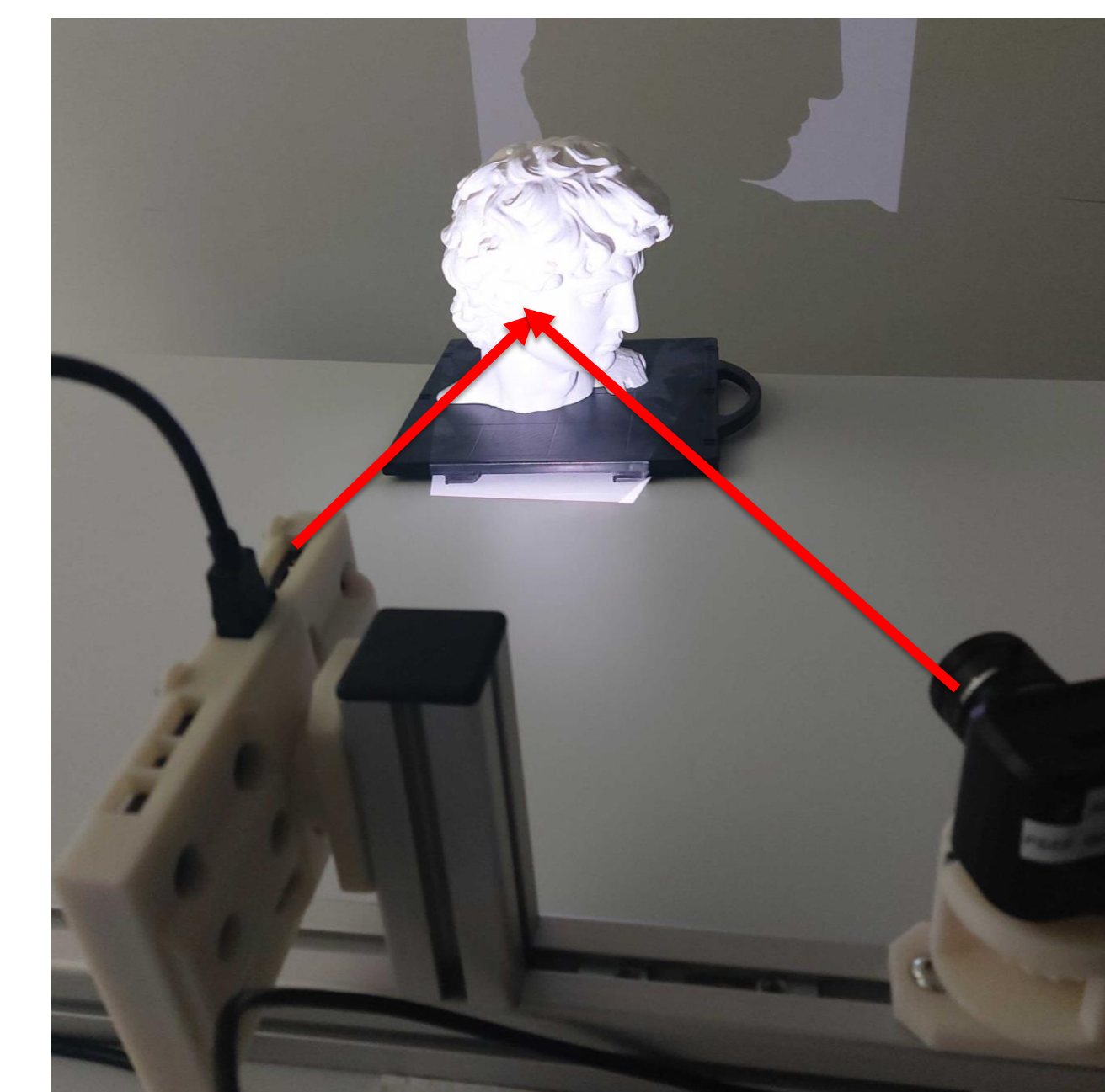
What is an Event Camera?



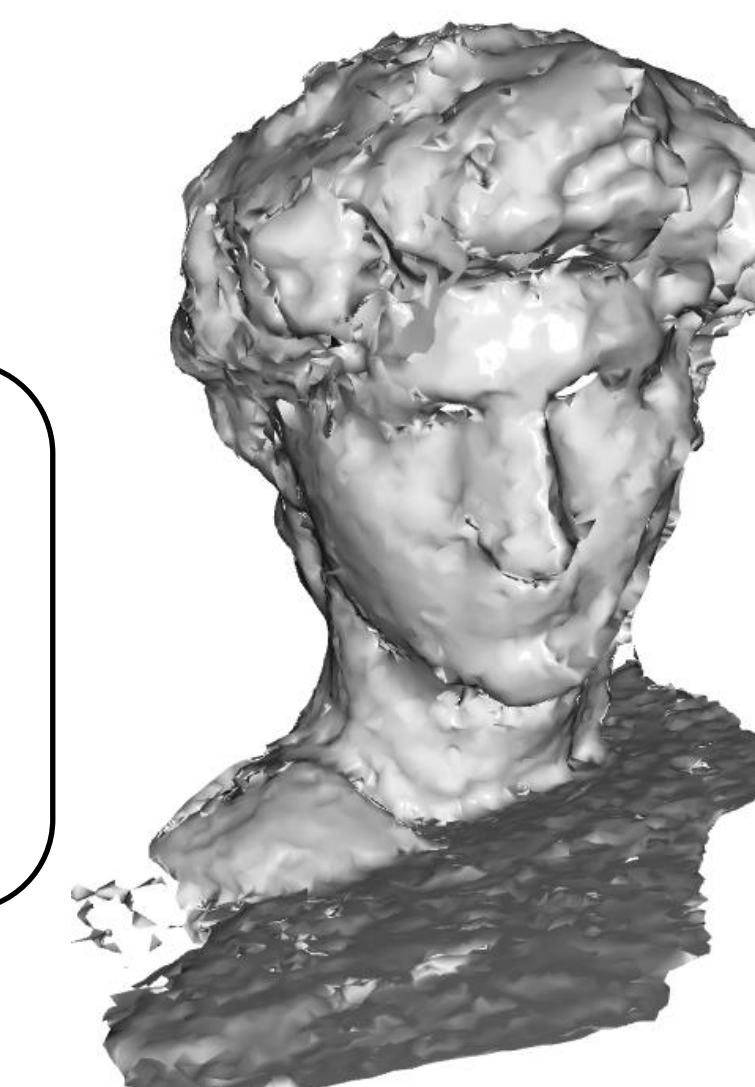
- Only transmits **brightness changes**
- Output is a stream of **asynchronous events**
- **Advantages:** low latency, no motion blur, HDR

Approach

Model the projector as an "inverse event camera"



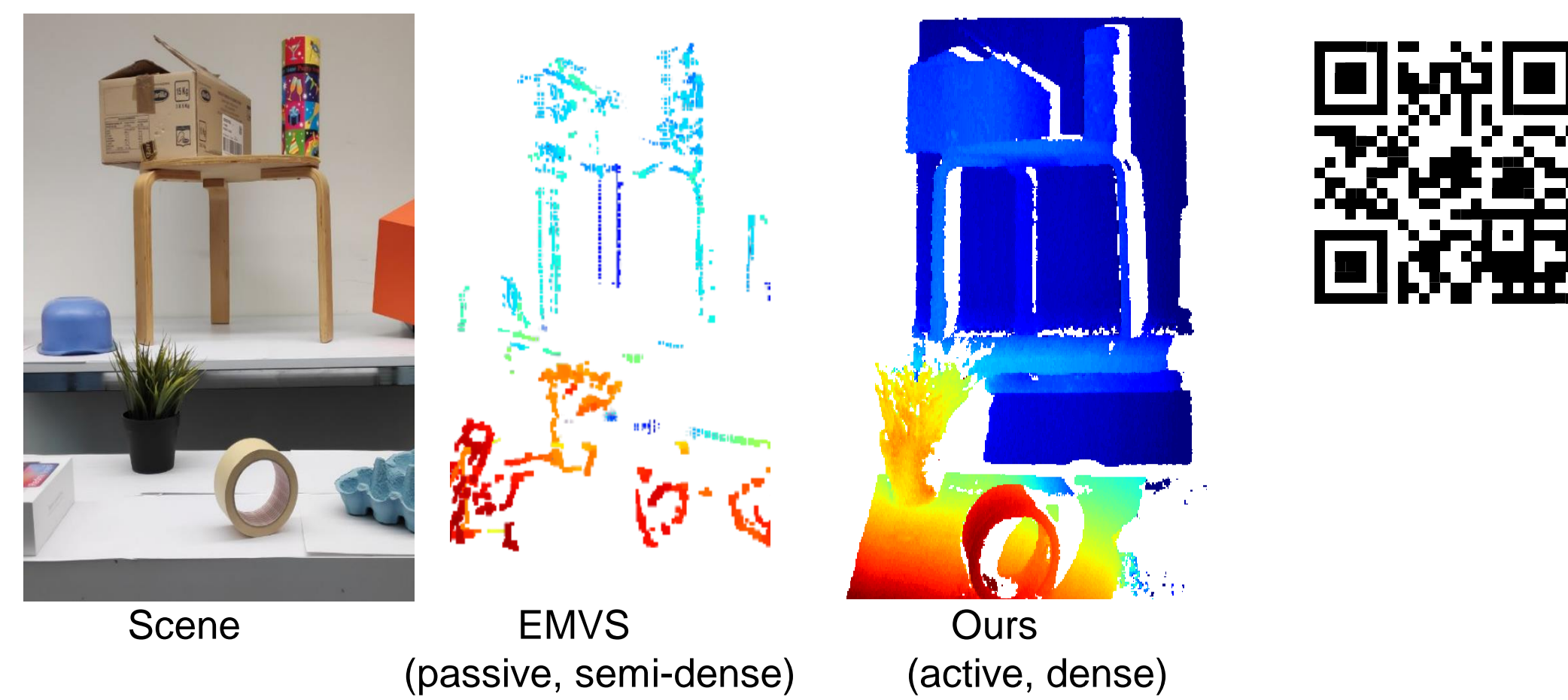
Dense 3D reconstruction



Scene	GT 1 s	MC3D 16 ms	SGM 16 ms	Ours 16 ms
Book-Duck				
City Lights				
Room				

Static scene reconstruction

Watch Video!



Sponsors



High-Speed Depth

- Evaluation on static scene shows **83% improvement** over SOTA in RMSE
- Qualitative comparison on **dynamic scenes** shows our method produces **smoother** depth and is **better** than commercial frame-based SL

Scene	MC3D 16 ms	SGM 16 ms	Ours 16 ms	Intel RealSense
Tape spin				
Fan				
Origami fan				
Air balloon				

HDR Scenes

Scene	Ours 16 ms	Intel RealSense
Ambient light		
Lamp light		
Floodlight		

Depth even in bright light!

Quantitative Analysis **NEW DATASET!**

Scene (Mean depth)	RMSE [cm]		
	Ours	MC3D	SGM
David (50cm)	0.46	14.81	1.08
Heart (50cm)	0.55	14.99	0.54
Book-Duck (49cm)	1.40	20.33	7.30
Plant (70cm)	1.97	24.73	5.21
City of light (90cm)	1.17	26.93	6.76
Cycle (90cm)	1.15	25.28	16.31
Room (394cm)	161.3	192.2	195.5
Desk-chair (171cm)	33.79	96.56	33.79
Desk-Book (151cm)	5.15	93.78	7.30