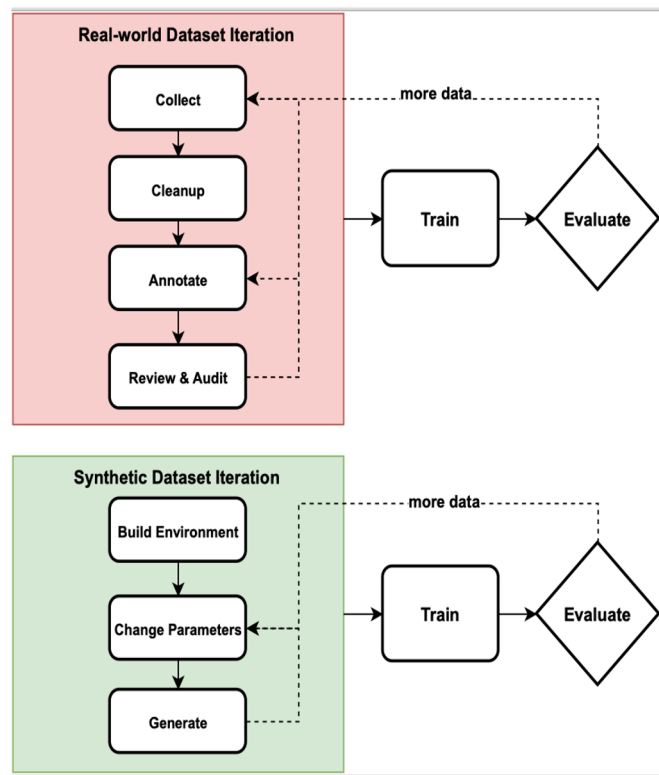
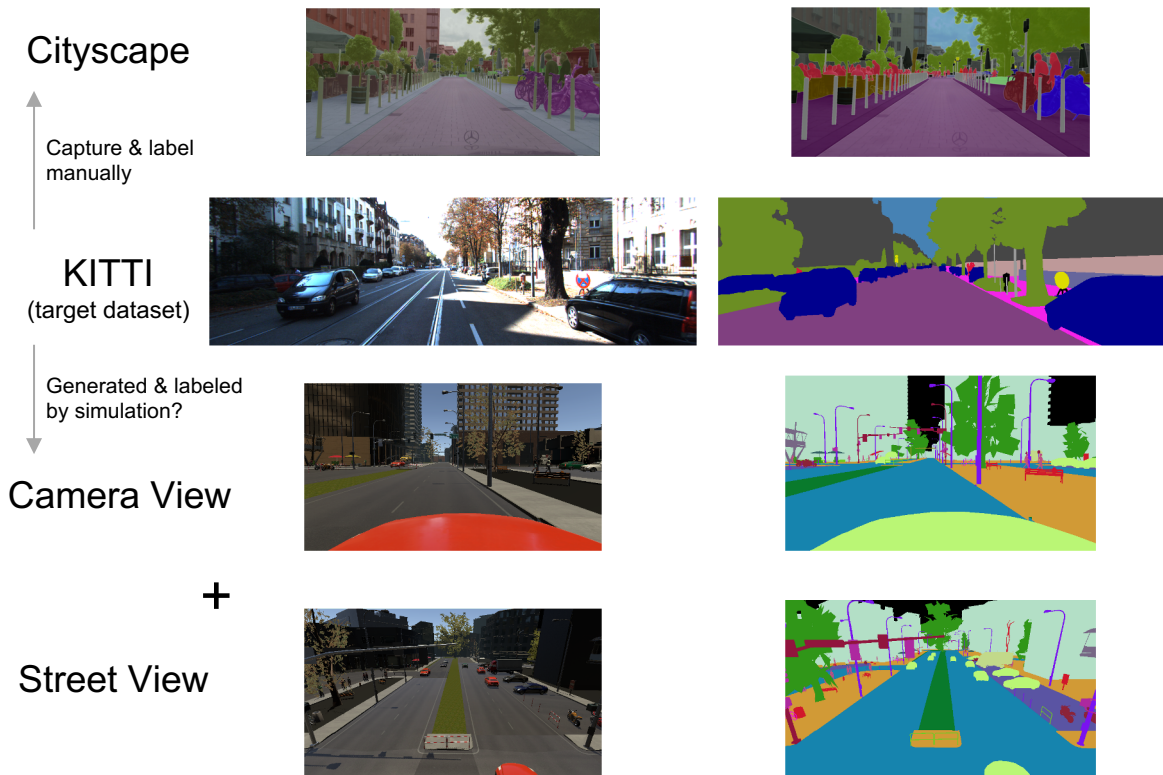


Simulation Data for Realistic Semantic Segmentation Model (Sim4Real)

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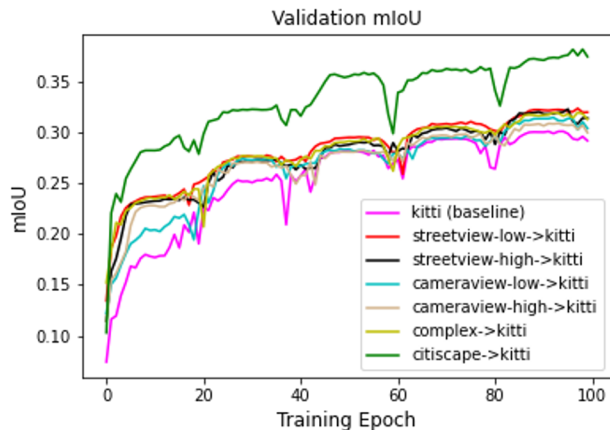
[1] Steve Borkman, Adam Crespi, etc. Unity Perception: Generate Synthetic Data for Computer Vision, 2021

[2] Geiger, Andreas, Philip Lenz, and Raquel Urtasun. Are we ready for autonomous driving? the kitti vision benchmark suite, 2015.

[3] Marius Cordts, Mohamed Omran, etc. The Cityscapes Dataset for Semantic Urban Scene Understanding, 2016.

Training Data	Val Data	Val mIOU
KITTI (baseline)	KITTI	0.394
Cityscape \rightarrow KITTI	KITTI	0.4338
streetview-high-res \rightarrow KITTI	KITTI	0.3945
streetview-low-res \rightarrow KITTI	KITTI	0.4014
cameraview-high-res \rightarrow KITTI	KITTI	0.394
cameraview-low-res \rightarrow KITTI	KITTI	0.3901
complex \rightarrow KITTI	KITTI	0.3847

Table 1. KITTI Validation Results. The high-res and low-res refer to high resolution and low resolution. The cityscape training model performance should be the performance upper bound of the simulation-generated data trained model if the cityscape and synthetic dataset share the same dataset size and distribution.



Conclusion:

- Simulation helps, but the gap exists.
Label Definition and Label Space.
- Street view helps, but the camera view does not.
Performance may be limited by the car's path and the camera's perspective from the car.
- Low-Resolution Simulation works better!
The details in simulation environment harm!
- Over-complex environment is hard to learn.
For a given environment, then just try to simulate the target environment.
Towards a more robust model, we may need more complex and varied simulations. (less happened and labeled cases can be solved in simulation)

Further Work:

- Active Data Acquisition
- Domain Adaptation Methods