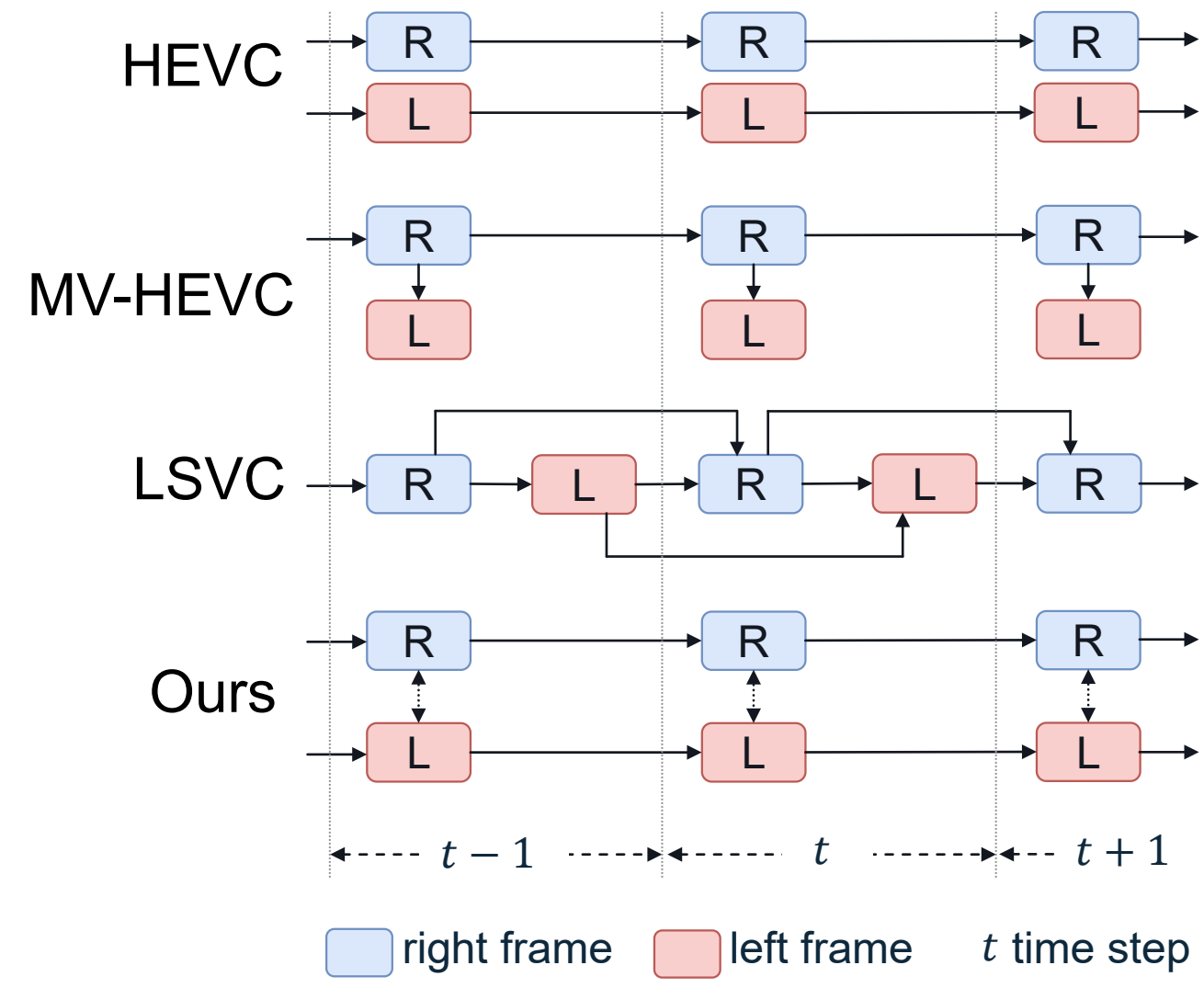


Overview

For both Automotive Vehicle (AV) and Virtual Reality (VR) applications, it is critical that the codec efficiently encodes stereo video while minimizing latency.



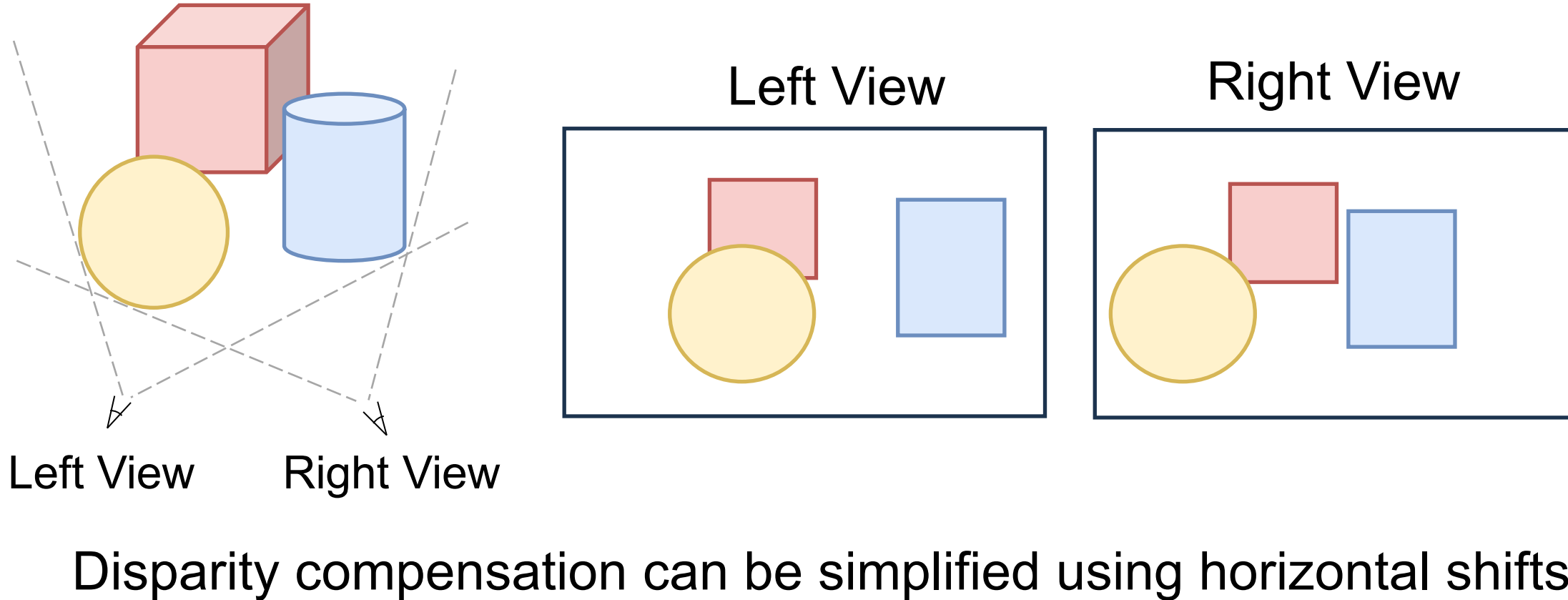
Autonomous Vehicles



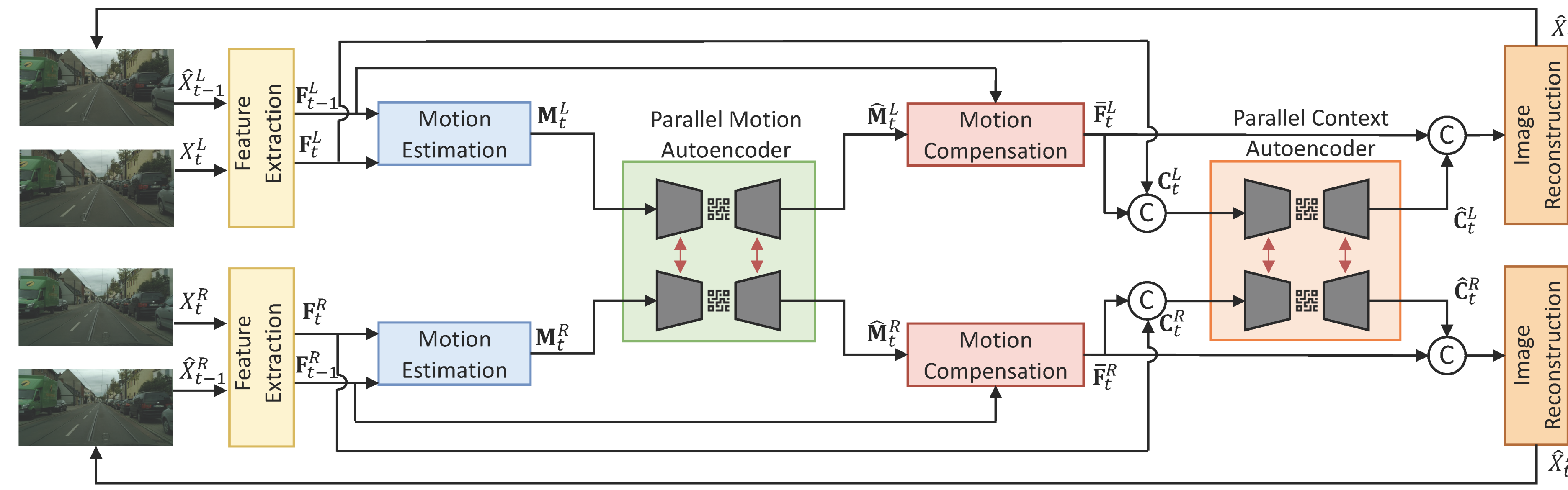
Contributions:

- 1) A novel low-latency neural stereo video codec architecture that replaces **sequential** inter-view compensation with an efficient and **parallelizable** learned module to connect parallel autoencoders
- 2) A **bidirectional shift module** that effectively captures and exhibits redundancy between inter-view features
- 3) Our method improves **50.6%** BD-rate savings compared to MV-HEVC on the cityscape dataset, and **2.8×** less complexity compared to LSVC.

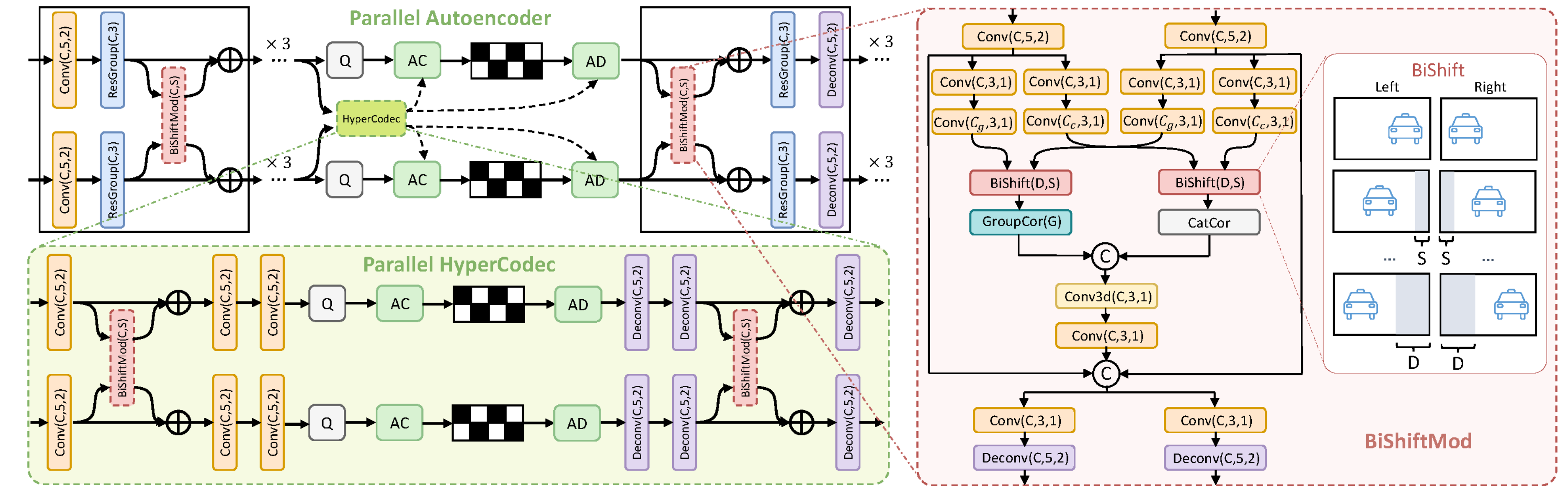
Motivation



Disparity compensation can be simplified using horizontal shifts



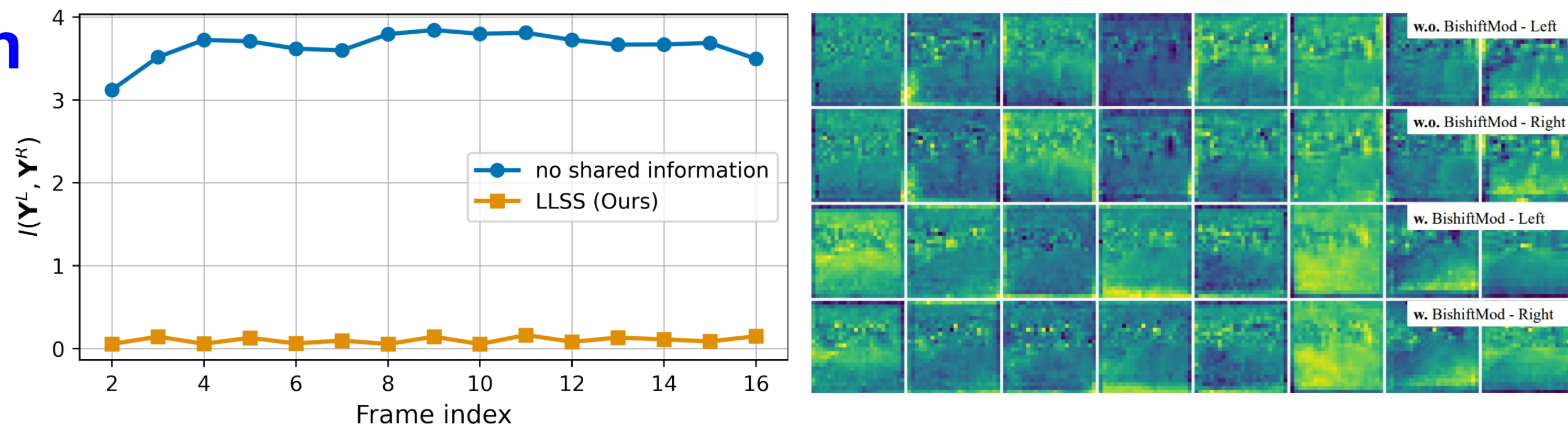
Our network incorporates a parallel motion autoencoder and a parallel context autoencoder to reduce the redundant motion and context information across views, respectively.



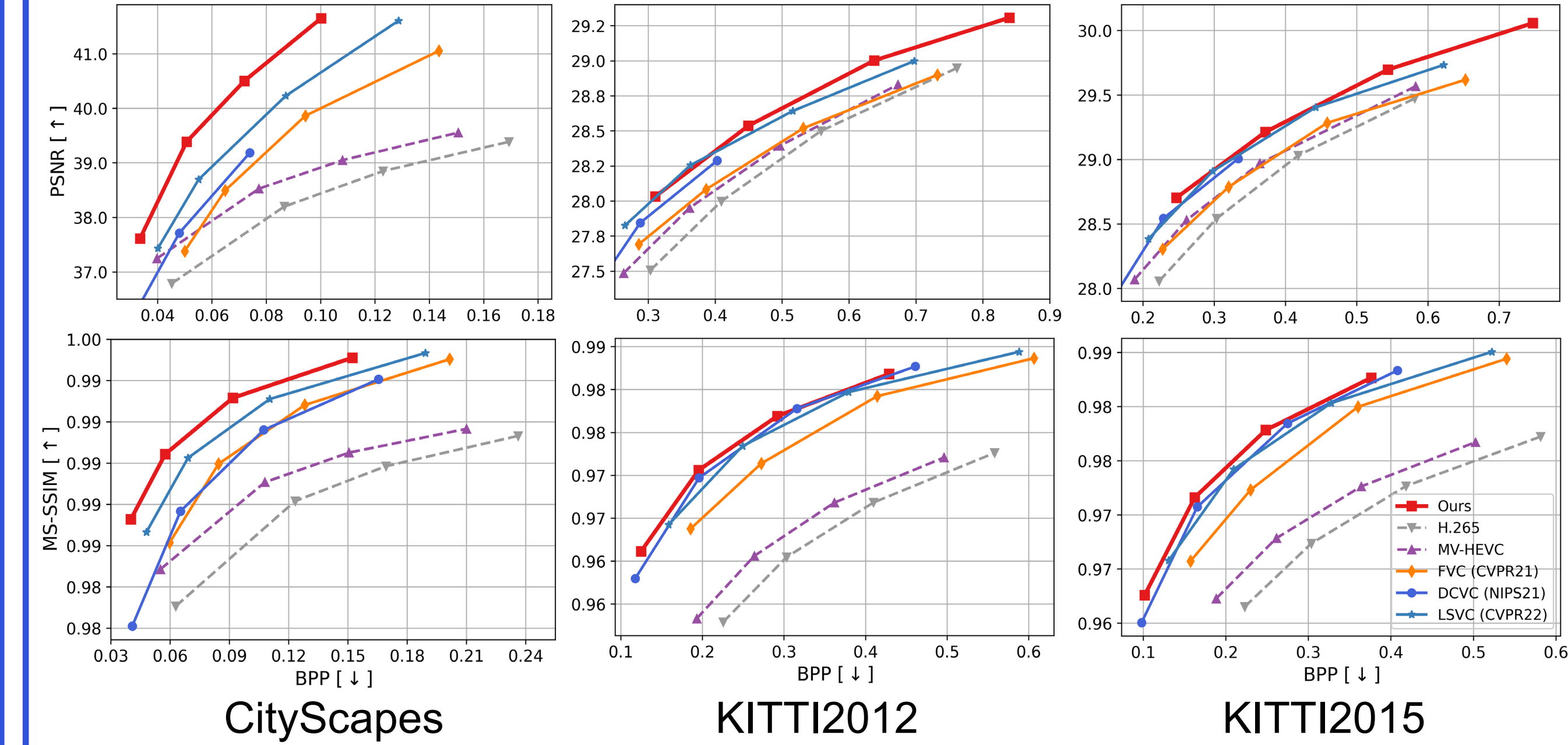
The Bidirectional Shift Module (BiShiftMod) shifts the left and right features bidirectionally.

Mutual information

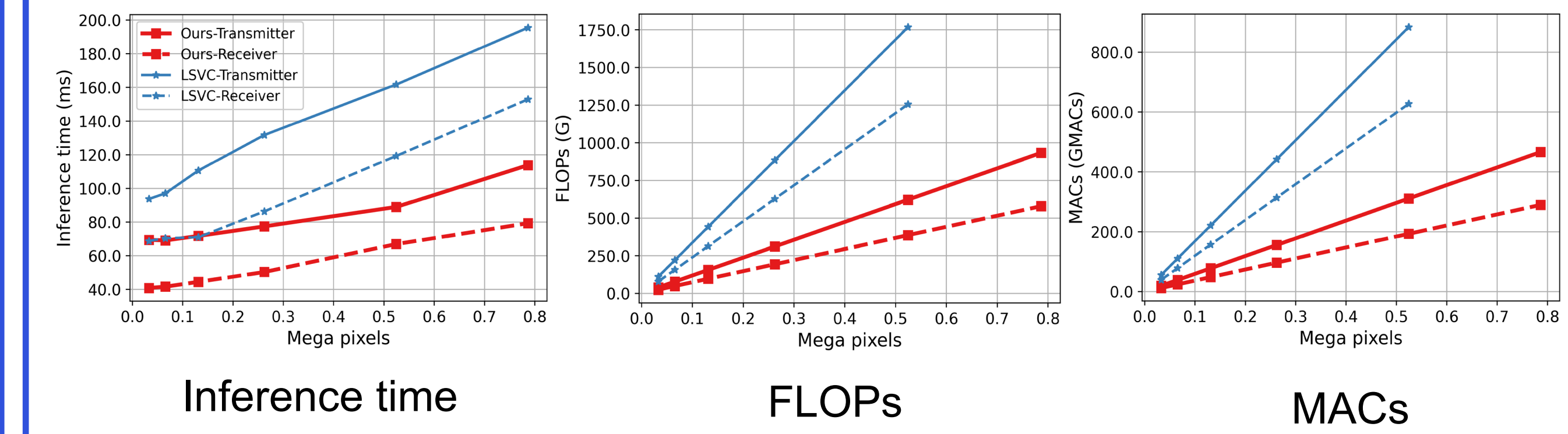
Mutual information between cross-view latent. With BishiftMod, the latent features between left and right views become less alike.



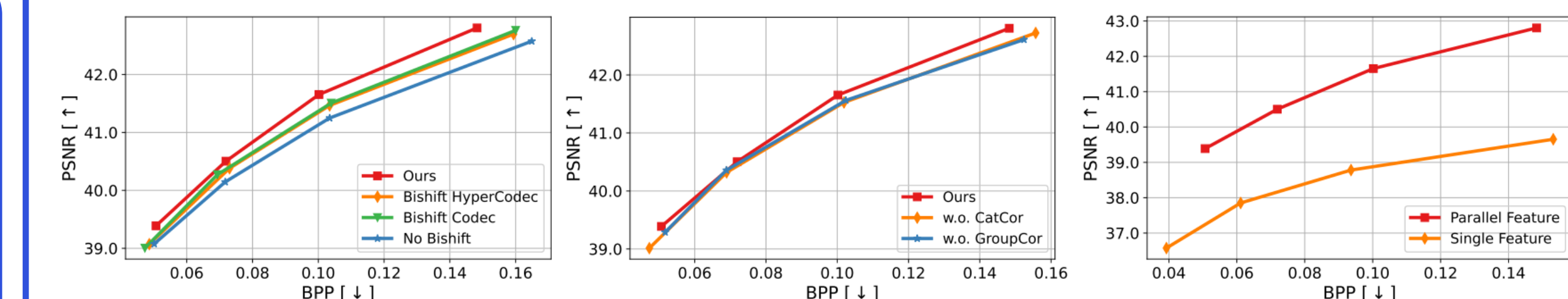
Experiments



Rate-distortion curves. On the CityScapes dataset, our method achieves **50.6%** BD-rate savings compared to MV-HEVC. On the KITTI 2012 and 2015 datasets, our method attains **18.2%** and **15.8%** BD-rate savings, respectively.



Computational complexity. Compared to LSVC, our method is 1.9×, 3.2×, 3.3×, faster in terms of the inference time, FLOPs, and MACs, respectively.



Ablation study. The effectiveness of the BiShiftMod, the components in BishiftMod, and the parallel feature

