

Stereo-Event-Camera-Technique for Insect Monitoring

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Abstract: To investigate the causes of declining insect populations, a monitoring system is needed that automatically records insect activity and additional environmental factors over an extended period of time. For this reason, we use a sensor-based method with two event cameras. In this paper, we describe the system, the view volume that can be recorded with it, and a database used for insect detection. We also present the individual steps of our developed processing pipeline for insect monitoring. For the extraction of insect trajectories, a U-Net based segmentation was tested. For this purpose, the events within a time period of 50 ms were transformed into a frame representation using four different encoding types. The tested histogram encoding achieved the best results with an F1 score for insect segmentation of 0.897 and 0.967 for plant movement and noise parts. The detected trajectories were then transformed into a 4D representation, including depth, and visualized.

1 INTRODUCTION

Climate and human-induced landscape changes have a major impact on biodiversity. One process that has been observed and scientifically documented in recent years is the decline of many insect species (Hallmann et al., 2017). To better understand the causes, biodiversity monitoring at the species level is needed, but is currently hampered by several barriers (Wägele et al., 2022). For example, automated species identification is difficult because only a limited number of test datasets for AI-based techniques for the various monitoring methods are currently available (Pellegriano et al., 2022). On the other hand, manual monitoring of insects is costly, which means that often only small areas and limited time periods are surveyed. Due to the high cost, such monitoring is only done on a random basis, so that comparisons for the same habitat type between regions or between different time periods are not possible. In addition, manual observations may be subject to unintentional bias (Dennis et al., 2006) and their quality may depend on the expertise of the observer (Sutherland et al., 2015). Furthermore, because the observational sources in this case e.g. as images of the measurements are not preserved, the accuracy of the data may be questioned later. This is especially true because human attention is low for non-foveal visual tasks and for moving objects (Ratnayake et al.,

2021).

Another problem is that even many automated methods (traps, camera-based systems) can only survey very small areas. The data thus obtained are not easily extrapolated to larger areas. In addition, species interactions or changes within populations are often difficult to detect due to the limited time window considered or the size of the observation patch. Suitable technologies for large-scale and long-term automated biodiversity monitoring are still lacking (Wägele et al., 2022).

For this reason, we want to develop a new monitoring method using event cameras. The operation and output paradigm of this sensor is fundamentally different from conventional cameras. For example, the event camera does not capture images at a fixed sampling rate, but generates event streams (Gallego et al., 2020). For each detected brightness change at a pixel position above a defined threshold, the x- and y-coordinate, a very precise time stamp t in microseconds and an indicator p for the direction of the brightness change are recorded. Other advantages compared to conventional CCD/CMOS sensors include higher dynamic range, lower power consumption, smaller data volume, and much higher temporal resolution. Since each pixel of an event camera operate independently and asynchronously based on relative brightness changes in the scene, they can also be used under difficult lighting conditions (strong brightness differences in the scene). First tests with this sen-

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Figure 1: Position of a bee (white dots) during takeoff in eight frames captured at 30 frames per second.

sor for insect monitoring have already been successfully performed (Pohle-Fröhlich and Bolten, 2023).

In this paper we want to discuss further developments of this approach. These major contributions are

- the use of a stereo event camera setup, so that 4D data points (x, y, z, t) can be recorded
- the investigation of different event encoding types for trajectory extraction
- the description of the depth calculation pipeline.

The rest of this paper is structured as follows. Section 2 gives an overview of related work. Section 3 describes the dataset acquisition setup. In Section 4, the currently used processing pipeline is explained and in Section 5, the obtained results are presented and discussed. Finally, a short summary and an outlook on future work is given.

2 RELATED WORK

The use of AI methods has significantly improved insect monitoring in recent years. Although the use of traps is still a common method for determining the biomass and abundance of individual insect species, whereas in the past traps were mostly evaluated by humans, this is now being done in part with the help of DNA metabarcoding (Pellegrino et al., 2022) or automated camera systems. The cameras capture single images of specific locations where insects are attracted by targeted lighting, colored stickers, or pheromones in order to identify and count them ((Qing et al., 2020), (Marcasan et al., 2022), (Dong et al., 2022)). During image acquisition, the insects

hardly move and can be well segmented due to the uniform background color used at these locations.

To detect interactions between different insect species, video cameras are usually used to examine small areas with very few plants. Under these conditions, good detection results can be obtained for some insects, such as bees ((Bjerge et al., 2022), (Droissart et al., 2021)). However, problems arise with trajectory detection (Figure 1), since required high temporal resolution cannot be used due to the required storage space. In addition, image compression (Figure 2) is required for long-term monitoring for the same reason, which makes insect detection difficult and error-prone.

The monitoring method proposed in this paper uses event cameras. Various approaches for segmentation and classification of event data can be found in the literature (Gallego et al., 2020). A common method for data analysis is to convert the event stream into 2D images. In this process, all events within a time window of fixed length or a fixed number of events are projected into an image using different encoding methods preserving different amounts of temporal information (e.g., binary encoding, linear time-surface encoding, polarity encoding). Then, different neural networks (e.g., U-Net, Mask-RCNN) are used for segmentation. In addition, neural networks that take a point cloud as input (PointNet++, LSA-Net, A-CNN) are used for both segmentation and classification ((Bolten et al., 2022a), (Bolten et al., 2023b)).

3 DATASET RECORDING SETUP

3.1 Used Sensor System

Contrary to the work of (Bolten et al., 2023b) on human activity recognition, the motion of insects does not take place on planes, but in 3D space. For this reason, capturing the scene with only one camera to estimate the z-coordinate as in (Bolten et al., 2022b) is not sufficient. Therefore, a stereo system was cho-



Figure 2: Poor visibility of a honeybee (see arrow) due to H.264 video compression.

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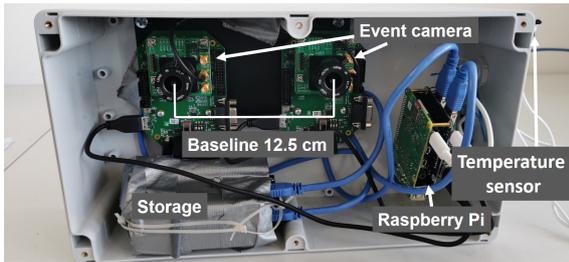


Figure 3: Stereo system with two event cameras.

sen for image acquisition. By capturing the depth information, it is also possible to make assumptions about the insect's size and flight speed and use them to group the insects. Figure 3 shows the setup of our measurement system.

Two parallel event camera IMX636 HD sensors distributed by Prophesee (Prophesee, 2023b) with an image resolution of 1280 x 720 pixels, each equipped with an 5mm wide-angle lens, are synchronized in time and connected to a RaspberryPi 4B running the data acquisition software. The event stream generated by each camera is written to an external hard drive. Additionally, a temperature sensor is integrated into the measurement setup. The camera system is powered by a portable power station, which can be recharged by a solar panel if required, to enable measurements in any terrain. Figure 4 shows our measurement system in action. For manual logging and labeling of insect activity, an additional event camera was connected to a laptop in order to display the reference data.

3.2 Covered View Volume

In order to obtain information about the detection range of our monitoring system, it was first determined by calculation. Subsequently, the theoretically calculated values were evaluated by throwing reference objects similar in size to certain groups of in-



Figure 4: System in action.

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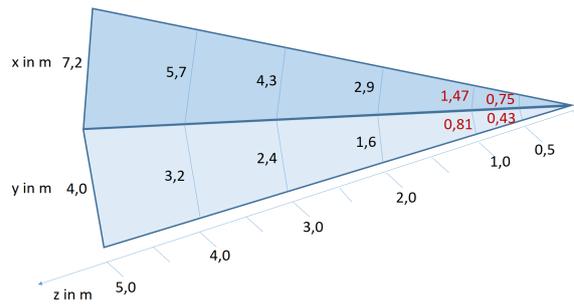


Figure 5: View volume.

sects at a defined distance into the field of view of the camera system. The measured values confirmed our calculations. Figure 5 shows the obtained view volume. The black numbers show the calculated values and the red numbers show the experimentally determined values.

Insects with a size of 5 x 2 mm², which is approximately the size of a mosquito, can be reliably detected up to a distance of 2 m from the camera. The area over which these insects can be reliably recognized is 2.9 m² considered in the top view. Insects with a size of 10 x 5 mm², which corresponds to the size of a house fly, can be reliably identified up to a distance of 5 m from the camera. These insects can be located on an covered ground area of 18 m². Insects with a size of 15 x 10 mm², which corresponds to the size of a honey bee, can still be reliably recognized at a distance of 7 m from the camera. In this case, the covered ground area is 35 m². This is a significant increase compared to the ground area of 1 m² used in manual insect counting.

3.3 Used Database

For the detection of insect flight paths, on the one hand, the labeled dataset from (Pohle-Fröhlich and Bolten, 2023) was used, which was, however, only recorded with one camera and not as stereo data. On the other hand, additional monocular event data were recorded and labeled. These recordings were taken in the evening in a garden with grass, and in the morning and in the afternoon on a balcony with flowers in balcony boxes. Because of the different scenarios, plant movement and other environmental factors varied.

All files were labeled to include two classes: Insect trajectory events and events due to noise and plant movements. Figure 6 shows a section of one of the labeled datasets, with the insect class events colored red and the environment class events colored white. Thus, eight recordings with a total dataset length of 10 minutes and 14 seconds were available for neural network training. The basic properties of

Table 1: Structure of the dataset.

No.	Content	Size in sec	No. of insect events	No. of other events
1	Meadow	30.94	834 373	1 109 131
2	Garden	100.01	1 054 489	200 102
3	Garden	97.40	1 022 401	137 577
4	Garden	156.58	935 939	545 659
5	Balcony	73.24	1 407 740	656 936
6	Balcony	61.12	160 504	756 339
7	Balcony	16.10	78 832	1 037 434
8	Balcony	78.85	1 407 740	656 936
		614.24	6 902 018	5 100 114

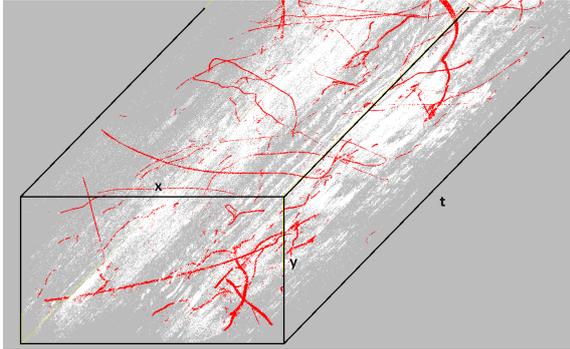


Figure 6: Example of the labeled insect dataset No. 1 (Events from flight paths are red and events from environmental effects are colored white.)

the dataset are shown in Table 1. It can be seen that the plant events are currently still slightly underrepresented.

4 FLIGHT PATH SEGMENTATION

4.1 Software Pipeline

The 4D trajectory determination for the individual insects is realized in several steps. After recording the event streams with the two cameras, they are first encoded into 2D frames for segmentation with a CNN. The events classified as insects are then transformed into rectified coordinates before the depth is calculated from the disparity of the pixels in each of two corresponding projected views from the left and right camera. Finally, the 4D points available after this step are visualized. The process is illustrated in Figure 7. The individual steps are described in more detail below.

4.2 Event Encoding

There are a variety of methods for encoding and processing the output stream of an event camera (Gallego et al., 2020). Often, the events are converted into classical 2D images and then processed using established image processing methods. This approach was also chosen for the insect data. Direct processing as a point cloud would require a reduction in the number of events by applying downsampling methods. However, since the insect trajectories represent very fine structures within the point cloud, these would be lost. Splitting the output data into different window regions, as in (Bolten et al., 2023a), would also be problematic because insects move very fast and thus fly over several windows in a very short time. The data would then have to be reassembled for final analysis. Since time information is lost when event data is projected into a 2D binary or polarity representation, various encoding methods have been described in the literature to preserve this information. Four different encoding approaches have been investigated for detection of flight trajectories.

- **Histogram encoding**

A simple way of encoding is to create a histogram. For a given time window, the number of events per pixel position is determined separately for each polarity, with the maximum number set to 5 (Prophesee, 2023a)¹. This results in a two-channel encoding. Fast moving objects, such as insects, have lower frequencies compared to slow and cyclically moving objects, such as plants. In the experiments performed, we used a time window of 50 ms for event accumulation.

- **Linear timesurface encoding**

The linear time surface is another method of encoding the time information of events in a 2D rep-

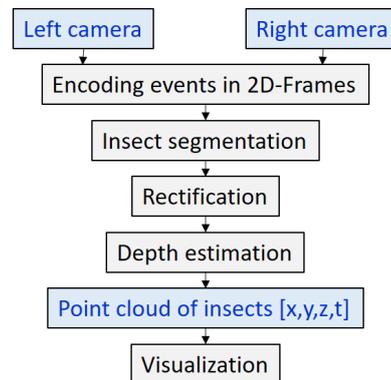


Figure 7: Software pipeline for detection of flight paths.

¹https://docs.prophesee.ai/stable/tutorials/ml/data_processing/event_preprocessing.html

resentation. In this method, the scaled time stamp of the last event that occurred is stored in each pixel, again considering the polarities separately. This yields to a two-channel encoding. The scaling is linear in the range between 0 and 255. In our experiments we used a time window of 50 ms.

- **Event cube encoding**

Event cubes were developed to combine the information from the histogram with the time information from the linear timesurface. In event cubes, each time bin is further divided into three micro time bins. Instead of counting an event based on its position and time stamp as in the histogram, the event is counted linearly weighted according to its time distance from the center of the neighboring micro time bins (Prophesee, 2023a)². Since the summation is done separately for each polarity. This results in a six-channel encoding and leading to a higher computational complexity for training and inference of neural networks compared to the other encodings. To obtain enough events in a frame for the calculation, a time window of 50 ms was used.

- **Optical flow encoding**

Finally, to encode the temporal information contained in the event stream, the optical flow was also examined, since insects usually move very fast and in arbitrary directions, while plants movements are slower and occur only in certain directions.

There are several ways to estimate optical flow. The algorithm provided in the Metavision SDK for computing sparse optical flow has the disadvantage that clustering is performed beforehand (Prophesee, 2023a)³. Experiments have shown that, for insect movements in the background with very few points in the projected image plane, no optical flow value is calculated.

For this reason, the dense optical flow algorithm provided by the Metavision SDK was used as well. Since the data from the insect crossings contains very few objects within a short time window, training the neural network used for the dense flow calculation did not produce satisfactory results, so we used a pre-trained network with the weights provided in the SDK for our calculations. As with the other methods, the time window for optical flow calculation was 50 ms. From the two predicted components of the flow vector, we have

²https://docs.prophesee.ai/stable/tutorials/ml/data_processing/event_preprocessing.html

³https://docs.prophesee.ai/stable/samples/modules/cv/sparse_flow_cpp.html

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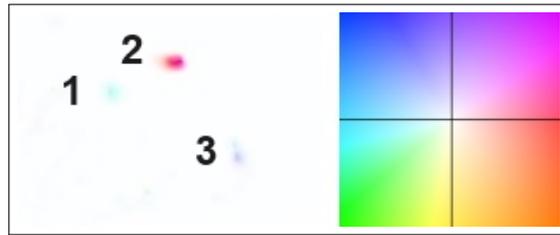


Figure 8: Example for optical flow prediction for three different moving objects. The adjacent color wheel was used for display. The intensity indicates the magnitude of the flow and the color the direction of the movement.

calculated the magnitude from this estimated velocity vector and direction as the angle to x-axis between 0 and 360 degrees. Again, resulting in a two-component encoding. It should be noted, however, that the computational cost of determining the optical flow is high. An example of the predicted optical flow can be found in Figure 8.

In our current investigations, all events in our dataset were encoded using the four encoding methods, resulting in a total number of 12230 images of each encoding.

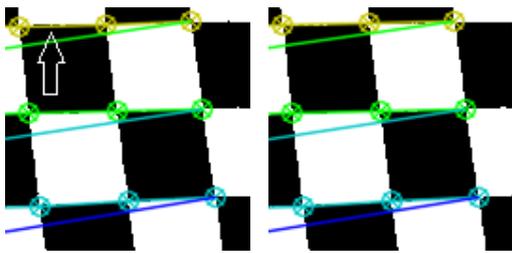
4.3 Insect Segmentation

After frame encoding, classical 2D networks can be used for semantic segmentation of trajectories. A typical network that can perform segmentation with a relatively small amount of input data is the U-Net (Ronneberger et al., 2015). It is an encoder-decoder network with a typical symmetric structure. The encoder part is used for feature extraction, where the convolutional and pooling layers also lead to down-sampling and information concentration, but also to spatial mapping reduction. Upsampling is then performed in the decoder section to restore the original size of the image and achieve high resolution segmentation at the pixel level. Upsampling layers are used here. In addition, there are skip connections between the encoder and decoder to integrate the features of the different layers of the encoder into the decoder.

The U-Net is a very lightweight network that has already been used to segment trajectories in (Pohle-Fröhlich and Bolten, 2023). For the segmentation with the U-Net, we used a network depth of four layers in combination with a loss function weighted by the class frequency of the individual pixels.

4.4 Camera Calibration

To facilitate stereo vision, the camera heads must first be calibrated. This serves the purposes of firstly undistorting the pixel coordinates, causing distances



(a) Points found in a single detection. (b) Average of multiple detections.

Figure 9: Comparison of a single detection and averaged object points.

between pixels to be unaffected by their positions in the pixel array, and secondly determining the cameras' exact position relative to one another. This allows us to align the event streams spatially and simplify the matching of corresponding events later.

Typically, calibration is performed by detecting readily discernible points of an object with a known shape and determining the transformation matrices matching these points' detected pixel coordinates with the presumed object point coordinates. For stereo calibration, a transformation is computed that maps the coordinate system of one camera to that of the other in addition to the undistortion transformation.

Commonly, a chessboard is used as the known object, detecting the inside corners between squares. For a frame camera, this can be a physical chessboard of which photos are taken at various angles and relative positions. Calibrating an event camera introduces the complication that events are only generated where there are changes in the scene. This results in a static chessboard not being captured by the camera. Moving a chessboard around in front of the camera would introduce motion and make it hard to acquire exactly corresponding object points. To record a pattern with an event camera without movement, it must change in brightness. One way to achieve this is by displaying the calibration pattern on a screen and making it flash. We displayed a flashing black and white chessboard on a white background on an IPS screen, causing events to be generated by the black squares. The dimensions of the squares were $2.2 \text{ cm} \times 2.2 \text{ cm}$. We use the Metavision SDK implementation (Prophesee, 2023a)⁴ to detect the inside corners in frames generated from 10 ms of events. To mitigate inaccuracies in corner localization, we take several static recordings of the chessboard from multiple angles and average the point positions of all detections for each individual recording. The result of

⁴https://docs.prophesee.ai/stable/api/python/core_ml/corner_detection.html

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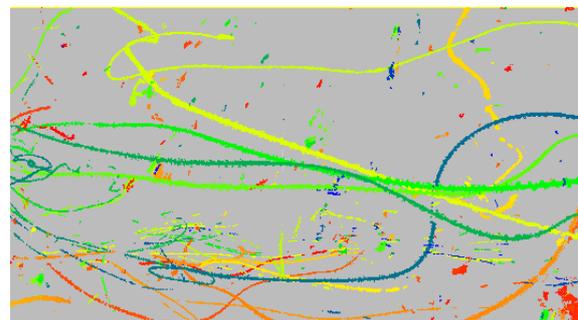
this approach is illustrated in Figure 9.

Once the object points are acquired, intrinsic and extrinsic camera parameters are calculated the same way as they would be for a frame based camera. We use the functionality provided by the Metavision SDK to calculate each camera's intrinsic parameters and use OpenCV (Bradski, 2000) library functions to acquire the extrinsic parameters based on the previously acquired object points.

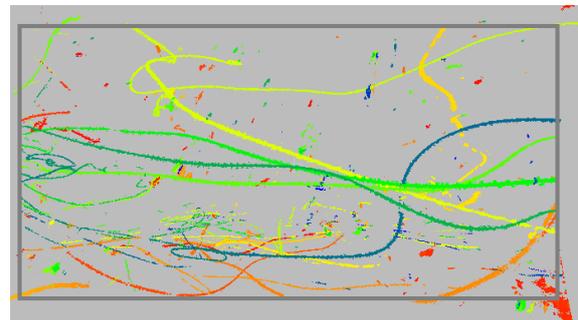
4.5 Depth Value Computation

The first step in the depth calculation after the camera calibration is the rectification of the images to ensure that by reducing the correspondence problem by the epipolar condition, the search for corresponding points only has to be done along one image row. The result is shown in Figure 10 for a part of the dataset.

The rectification is followed by a search for corresponding point pairs. For this purpose, the events detected as insects in the two camera streams are projected into an image over a longer time period of empirically determined 250 ms each, where the value at the pixel position corresponds to the time stamp (see Figure 11). The differences in the trajectories seen in the figure between the left and right camera images

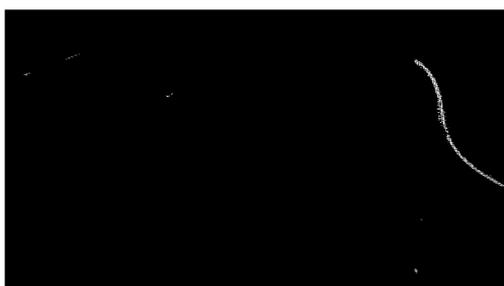


(a) Plain display.



(b) Data after rectification.

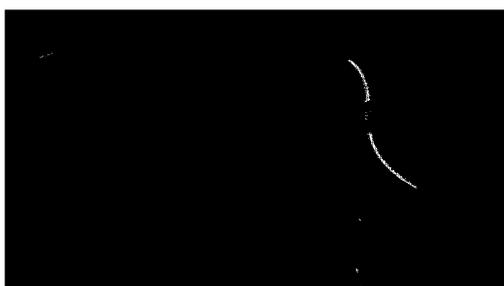
Figure 10: Part of a dataset before and after the rectification step (the frame indicates the undistorted section, and the colors of the individual events correspond to the time stamp).



(a) Image of the left camera.



(b) Image of the right camera.



(c) Image with the detected corresponding points.

Figure 11: Left and right images and detected corresponding points.

may be due to either differences in occlusion during perspective projection from different viewing angles, or differences in segmentation.

To determine depth, for each pixel in the right image, a corresponding pixel in the left image is located, including not only the same row but also two rows below and above to account for calibration inaccuracies. A pixel is considered corresponding if the time difference is minimal and less than 1.5 ms. This threshold is empirically determined and compensates for inaccuracies during synchronization. The difference of the x-coordinate between the determined corresponding values is stored as a disparity value. In the last step, the 4D world coordinates (x , y , z , t) are calculated from these disparities and the reprojection matrix determined during camera calibration, where the

coordinates are relative to the optical center of the left camera.

5 RESULTS

To evaluate the different encoding methods with respect to the quality of the segmentation, the dataset described in Section 3.3 was used, which, however, does not contain any stereo data. To evaluate the quality of the depth estimation, two additional datasets were used. However, no segmentation ground truth was available.

5.1 Segmentation Results

To investigate the segmentation quality, our dataset of 12230 images was partitioned using 3690 images as a test set. To ensure that the network had not already seen immediately adjacent images, the total number was first divided into blocks of 10 images each, from which 369 blocks (30%) were randomly selected. Each block contained a time interval of half a second. Due to the fast movement of the insects, this ensured sufficient variability between training and test sets.

To compare segmentation results the F1 score was used. The best results were obtained with histogram encoding after 100 training epochs. The individual results are shown in Table 2a. The F1 scores for the BACKGROUND class representing pixels in the encoding without any triggered events were 0.999 in all cases and are therefore not included in the table.

When looking at the result images, it became clear that the two classes of interest were mostly segmented slightly too large, resulting in a low F1 value. Therefore, only those class predictions where events actually occurred were considered in a post-processing step. This makes sense because only these are important for propagating the results back to the original 3D event stream for depth estimation (Pohle-Fröhlich and Bolten, 2023). The results of this post-processing are given in Table 2b. The F1 values improved for all classes and encodings. Again, the best results were obtained for the histogram encoding.

Using the trained weights to predict events associated with insect flight paths yields to similar results for two datasets taken from different views of a meadow (Figure 13b) that were not included in the training set. Figure 12 shows a section of the point cloud visualizing all events for three of the used encoding methods. All points detected by event cube encoding are colored red, all detected by optical flow encoding are colored green, and all detected by his-

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Table 2: Resulting F1 scores for different encoding methods.

class	Environment	Insect
histogram	0.910	0.662
linear time surface	0.500	0.633
event cube	0.891	0.665
optical flow	0.490	0.663

(a) Plain inference after 100 epoch training.

class	Environment	Insect
histogram	0.967	0.897
linear time surface	0.956	0.857
event cube	0.912	0.755
optical flow	0.945	0.807

(b) Results after post-processing.

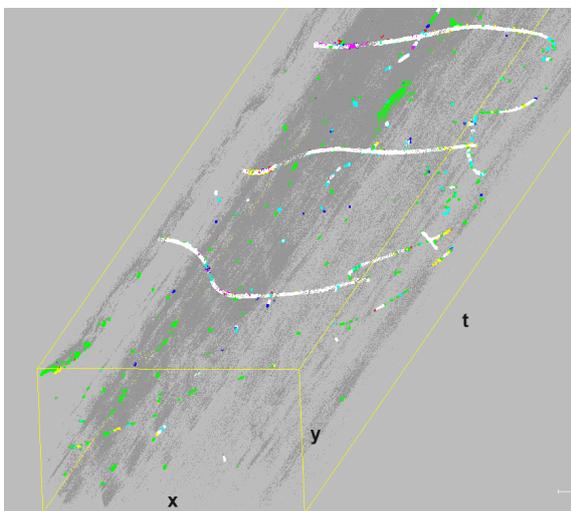
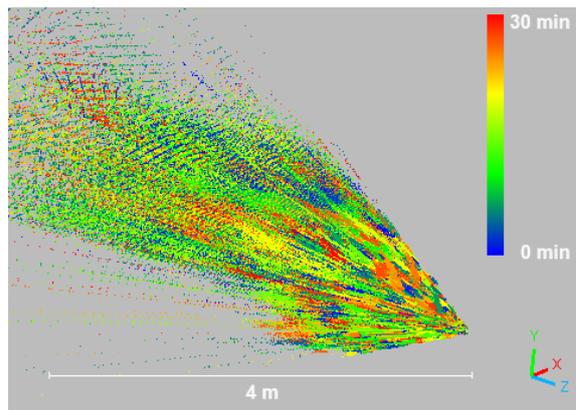


Figure 12: Result of the prediction for the dataset of the meadow in direction 1 using the different encoding methods (red: event cube encoding, green: optical flow encoding, blue: histogram encoding). All other colors result from additive color mixing. For the detected environmental events, a value of 50 was additionally used for the alpha channel.

togram encoding are colored blue. All other colors result from additive color mixing. Events shown in white were predicted to be part of the insect flight path by all three encodings. All black events were classified as noise or part of the plant movement by all methods. It can be seen that the optical flow encoding incorrectly predicted many events of plant movement, while the event cube encoding often failed to detect parts of the insect trajectory. The best results (blue, white, magenta and cyan markers) are provided by histogram encoding.



(a) All trajectories in 30 minutes for the meadow in view direction 1.



(b) Considered meadow with the two directions of view used.

Figure 13: Detected trajectories in a time interval of 30 minutes for the considered meadow shown below.

5.2 Depth Estimation Visualization

The visualization of the data from two 30-minute recordings of a meadow in two different view directions is based on the computation of the 4D data using histogram encoding. Figure 13a shows all insect movements over 30 minutes in the first recording. In the displayed view volume, the time is coded by the color. It can be seen that insect flight occurred anywhere up to 4 meters in the meadow during the recording.

Beyond about 4 m from the camera, the data thinned out, partly due to inaccuracies in the camera calibration and partly due to the chosen position of the camera just below the tallest plants (Figure 13b). The trajectories determined at shorter time intervals for the two different views of the meadow are shown in Figure 14 to better assess the quality of the results.

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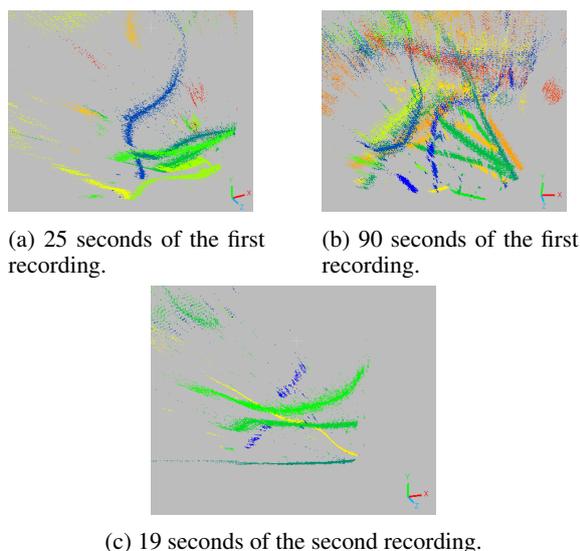


Figure 14: Trajectories of the first recording of a meadow over 25 and 90 seconds and the second recording over 19 seconds.

6 CONCLUSIONS AND FUTURE WORK

This paper presents the steps of the developed processing pipeline from image acquisition to 4D display for long-term insect monitoring with a stereo event camera setup. Segmentation results have shown that insect trajectories can be reliably separated from plant movements. The use of histogram encoding gave the best results. To improve the segmentation, besides the improvement of the dataset a Siamese neural network will be tested, which uses the same weights but works in parallel on the two different input images to obtain comparable segmentation results. This could compensate for differences in segmentation quality between the left and right camera images.

There are still some inaccuracies in the calculation of the 4D coordinates. These are caused by the construction of the measurement system. The alignment of the two event cameras changed slightly due to transport and heat, so that using the calibration data resulted in an offset of up to 10 lines, depending on the position of the events in the pixel matrix. A more mechanically stable setup will be developed in the future. For further interpretation of the data, the next step will be to cluster the individual trajectories and convert them to spline curves in order to obtain better 3D flight curves. Methods for trajectory tracking will also be investigated in order to obtain longer sections and to avoid double counting of insects. Finally, the individual trajectories will be classified into different insect groups based on the flight patterns as proposed in (Pohle-Fröhlich and Bolten, 2023).

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