

Multisensory Perception: From Integration to Remapping



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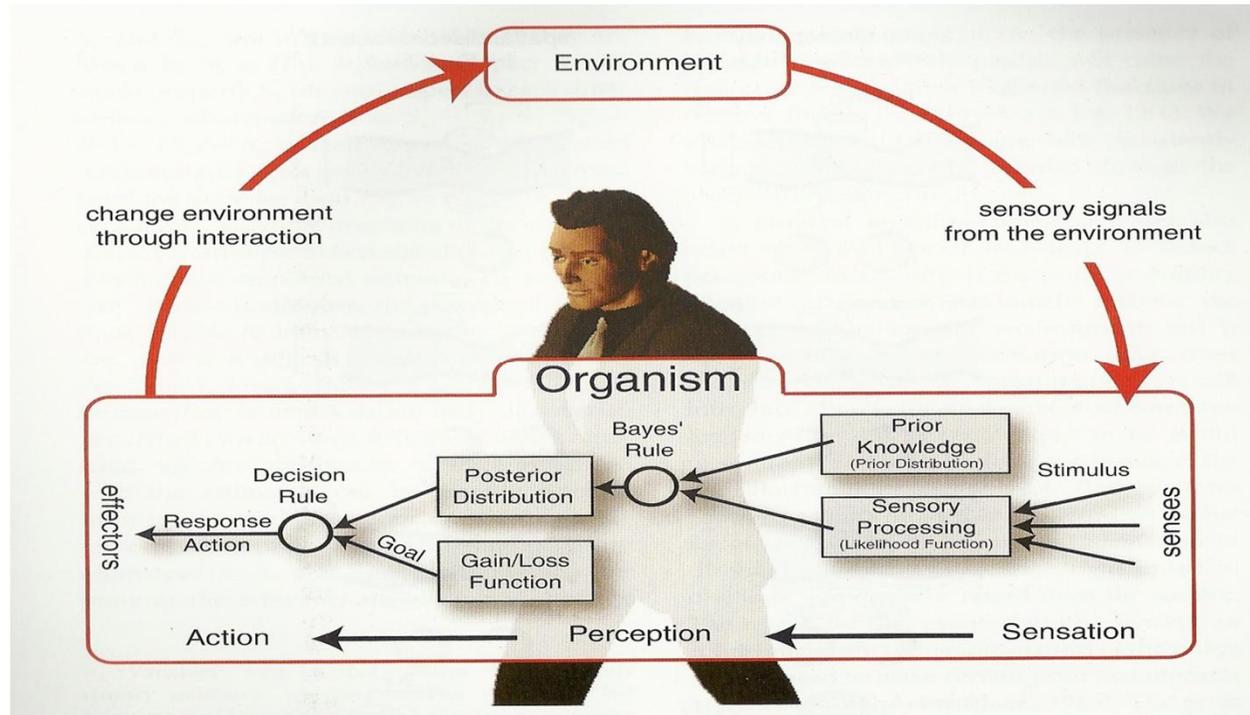
Quiz



- ❖ What cause D (discrepancy) between the cue estimates and in what situation would remapping happen?

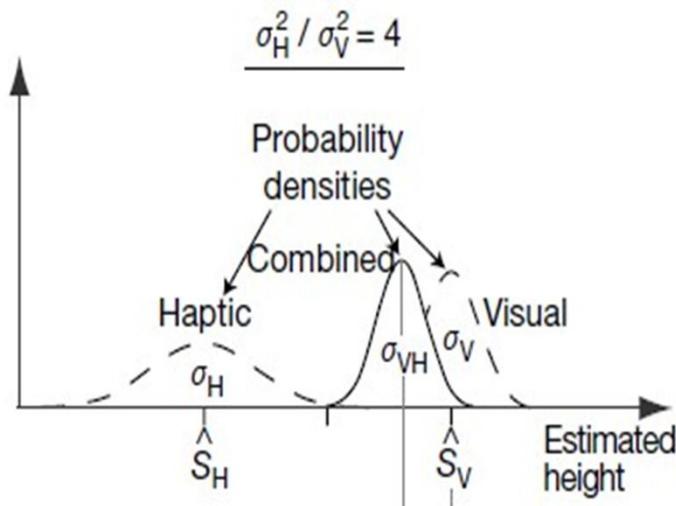
The reason for the discrepancy could either be a difference between signals or a random noise perturbation. If the discrepancy is consistent, we could adapt to the discrepancy, which process is called remapping.

The action/perception loop



The action/perception loop schematically illustrates the processing of information according to Bayesian decision theory.

Multisensory Integration



Visual and haptic estimates are combined to determine the size of an object.

❖ Assumption

An observer has access to **accurate estimates** of a particular world property from each cue.

The cues are Gaussian distributed (Gaussian noise) and conditionally **independent**.

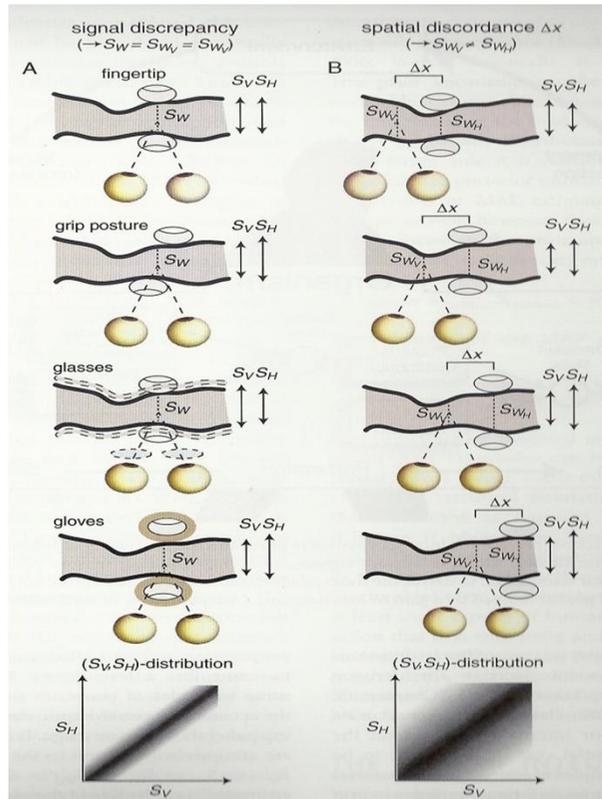
$$\hat{S}_{VH} = w_V \hat{S}_V + w_H \hat{S}_H, \text{ where } w_V + w_H = 1$$

$$w_j = \frac{r_j}{\sum_i r_i}$$

$$r_i = \frac{1}{\sigma_i^2}$$

cue's reliability (r) (inverse proportion of variance (σ^2))

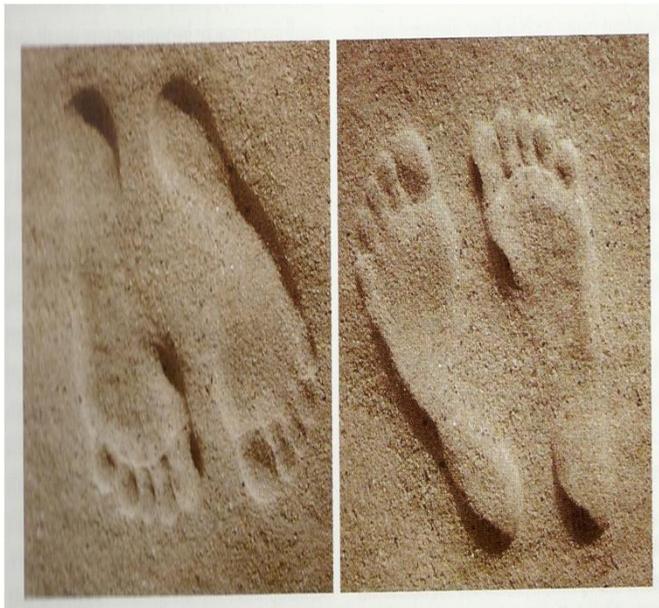
The cost of integration



The cost is the introduction of **potential biases (inaccuracy)** into perception.

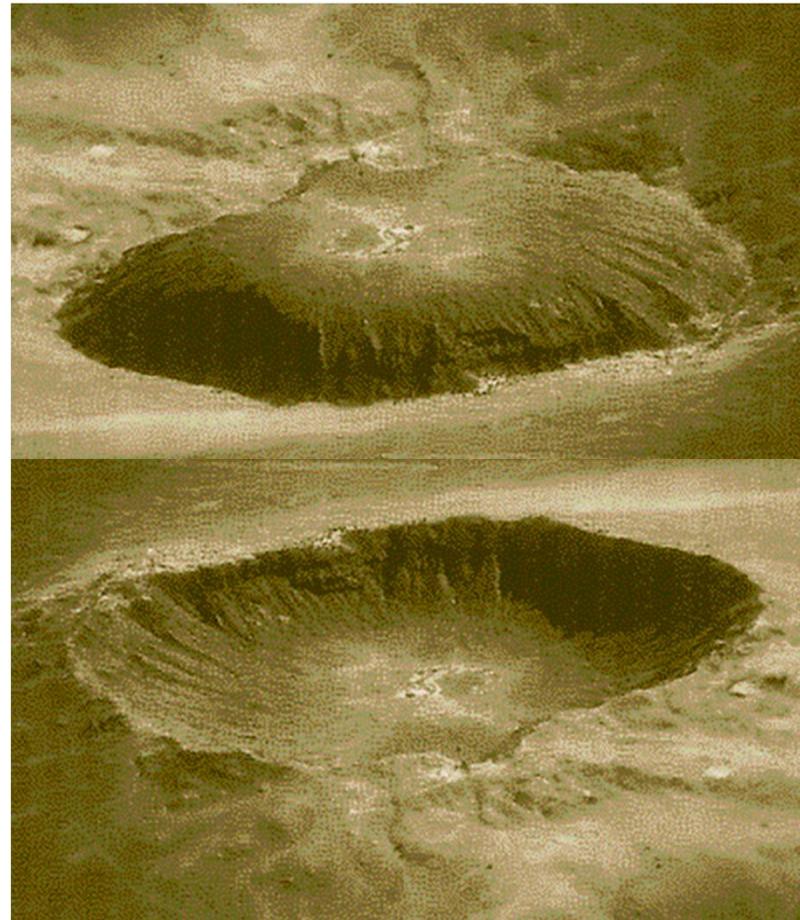
Picture A give some examples of **signal discrepancy** while picture B give some examples of **spatial discordance**.

The cost of integration



This picture illustrate the discrepancy caused by **prior knowledge**.

We normally assume that light is coming From **above**.



Balancing benefits and costs



- ❖ Whether to integrate different multisensory depends on the presence of an actual difference **D(discrepancy)** between the multiple sensory signals.
- ❖ The reason for the D(discrepancy) could either be a difference between the signals or a random perturbation as a result of noise. Since both possibilities are plausible and have associated uncertainty, the optimal strategy would be to use them both and weight each according to its relative certainty.