CrossFuse: Robust IR–Visible Fusion via Self Supervision with Top-k Alignment

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Abstract- In multimodal image fusion, robust generalization across diverse environments remains a significant challenge—especially under label-scarce conditions and out-of-distribution (OOD) shifts. We propose CrossFuse, a novel self-supervised learning (SSL) framework for infrared (IR) and visible image fusion, combining multi-view augmentations with a Top-k Selective Vision Alignment (SVA) mechanism. CrossFuse leverages weakly aggressive augmentations to maintain modality integrity while encouraging robust feature interactions. At its core, CrossFuse introduces a cross-modal contrastive loss with Top-k mining, enabling adaptive feature selection and improved cross-sensor alignment. Through extensive experiments on challenging benchmarks such as FLIR ADAS and MFNet, CrossFuse consistently outperforms existing fusion techniques in both in-distribution and OOD scenarios. Our approach is fully label-free, enabling scalable and generalizable multimodal training. This work paves the way toward more resilient sensor fusion systems, with potential implications in autonomous navigation, remote sensing, and surveillance.

Index Terms Multimodal Image Fusion, Self-Supervised Learning (SSL), Top-k Vision Alignment, Cross-Modal Contrastive Learning.

1 INTRODUCTION

1.1 Multispectral Imaging and Fusion

Multispectral imaging leverages different spectral bands—most notably infrared (IR) and visible light (RGB)—to capture complementary scene information. While visible light sensors provide rich color and texture under adequate lighting, IR sensors detect thermal radiation, making them invaluable for night-time imaging, obscured visibility, and temperature-based object detection. By fusing these modalities, systems can gain a more holistic and resilient understanding of a scene.

The fusion of IR and visible imagery is particularly relevant in applications such as:

- Autonomous driving, where IR aids in detecting pedestrians or vehicles in low visibility.
- Surveillance, enabling object detection even under night-time or foggy conditions.
- Disaster response and military systems, which require situational awareness across diverse environments.

1.2 Challenges in IR–Visible Image Fusion

Despite their complementarity, IR and visible images differ significantly in:

- Spectral properties: IR captures heat signatures; RGB reflects light intensity.
- Feature structures: IR often lacks texture and edge detail; RGB can lose contrast under poor lighting.
- Data distributions: These can vary across sensors, scenes, and environmental conditions.

This results in a heterogeneous feature space, making naïve fusion strategies (e.g., pixel averaging or simple concatenation) suboptimal or even detrimental.

Moreover, label scarcity is a major bottleneck. Building supervised fusion systems requires pixel-level aligned IR-RGB pairs with corresponding ground-truth annotations—a resource-intensive process. Additionally, most supervised models are vulnerable to distributional shifts, performing poorly on unseen environments, sensor configurations, or lighting conditions.

1.3 Rise of Self-Supervised Learning (SSL)

Self-Supervised Learning has emerged as a powerful solution to reduce dependence on labeled data. By designing pretext tasks—such as contrastive learning, instance discrimination, or reconstruction—models can learn discriminative representations from raw data alone. SSL approaches like SimCLR, MoCo, and BYOL have shown competitive or superior

performance to their supervised counterparts on various vision benchmarks.

However, these SSL strategies have been primarily focused on unimodal RGB data. Extending them to cross-modal or multimodal domains introduces new complexities:

- Pretext tasks must preserve and respect inter-modal relationships.
- Augmentations must not degrade the alignment or semantic consistency between modalities.
- Fusion must balance shared and modality-specific features.

1.4 Limitations of Existing Fusion Approaches

Most traditional IR-visible fusion techniques adopt encoder-decoder architectures trained under supervision. Some rely on handcrafted fusion rules (e.g., averaging, max pooling, wavelet fusion), while more recent models employ attention mechanisms or feature concatenation to merge modalities.

Despite progress, these methods:

- Struggle with generalization to OOD data.
- Often overfit to specific sensor domains or lighting conditions.
- Fail to adaptively select semantically meaningful regions across modalities.

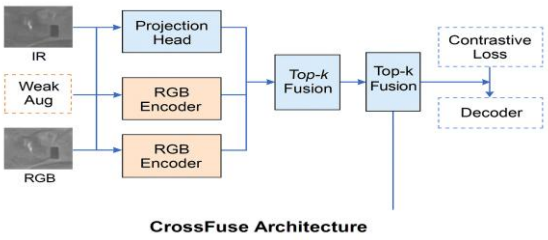
Furthermore, SSL-based fusion models are still in their infancy. Current multimodal SSL approaches tend to treat all modality features equally, ignoring the fact that some regions may carry more reliable information in one modality than the other—a key insight driving our proposed Top-k strategy.

1.5 The Need for Robust, Unsupervised Fusion

The evolving landscape of real-world applications calls for:

- Label-free fusion models that scale without costly annotation.
- Selective and adaptive alignment mechanisms that can differentiate useful signals from modality-specific noise.
- Fusion strategies resilient to OOD shifts, sensor noise, and varying environments.

Our work addresses these needs through CrossFuse, a novel SSL-based framework that integrates Top-k Selective Vision Alignment and Weak Aggressive Augmentation to robustly learn multimodal representations that generalize across tasks and domains.



CrossFuse Architecture

2. LITERATURE REVIEW

2.1 Self-Supervised Learning Techniques

Self-supervised learning (SSL) has become a cornerstone for representation learning, especially when labeled data is scarce. Models like SimCLR, MoCo, and BYOL leverage contrastive learning and data augmentations to build robust visual embeddings without labels. These have been extended to remote sensing images (e.g., RGB, IR, multispectral) via frameworks like Contrastive Multiview Coding (CMC) to learn scene representations from unlabeled data

Recently, self-supervised fusion techniques have appeared. For instance, Ofir & Nebel (2023) proposed unsupervised IR–NIR fusion trained on a single pair via structural similarity losses Zhao et al. (2022) introduced interactive feature embedding for IR–visible fusion in an SSL framework to preserve modality-specific details

While SSL advancements in transformer-based vision-language models (e.g., ViLT, FLAVA, BEiT-3) demonstrate powerful cross-modal alignment capabilities few directly translate to fine-grained pixel-level fusion tasks like IR–visible image fusion.

2.2 Multimodal Fusion Approaches

2.2.1 Traditional and Deep Learning Fusion

Classical fusion techniques include wavelet transforms, PCA/ICA, and NMF, designed for pan-sharpening and multispectral imagery Wavelet-based methods (e.g., Contourlet, Curvelet) capture high-frequency details effectively.

Deep learning has since dominated IR–visible fusion. Convolutional autoencoders and CNNs (e.g., IFCNN, DenseFuse, U2Fusion) enable end-to-end learning, preserving both texture and thermal information. Adversarial methods (e.g., FusionGAN, DDcGAN)

utilize generative priors to enhance realism in fusion .Transformer-based or attention-infused fusion frameworks (e.g., GANMcC, RFN-Nest, FusionGRAM) demonstrate the strengths of self-attention in balancing cross-modal feature integration

2.2.2 Attention-Guided and Selective Fusion

To address modality imbalance, pose-adaptive and saliency-based fusion techniques (e.g., CMAFF) model relationships between common and differential features for better alignment. Multi-weight or gated fusion frameworks further learn to adjust feature importances dynamically, but often rely on labeled supervision.

2.3 Joint SSL and Multimodal Frameworks

Unsupervised strategies have made strides by combining contrastive learning with spatial or spectral priors. Liu et al. (2021) imposed deep spatial-spectral priors for multispectral fusion. In remote sensing, self-supervised gated multimodal transformers (MGSViT) combine SAR and multispectral data Still, existing joint frameworks largely treat modalities equally and depend on global alignment, leaving local feature reliability underused. They seldom incorporate mechanisms to selectively weight or attend to the most semantically aligned features, which is critical in heterogeneous modalities with noise/distribution shifts.

2.4 Gaps in Current Research

From the review above, several key limitations persist:

1. Supervision-heavy fusion: Most deep-fusion models require labeled data, limiting adoption in low-label domains.
2. Insufficient self-supervision: SSL approaches remain largely unimodal or high-level, with limited pixel-level cross-modal consistency.
3. Uniform fusion schemes: Neglect top-k signal selection—fused representations treat all regions uniformly, even when some are noisy or misaligned.
4. OOD vulnerability: Methods often overfit to specific sensors or environmental conditions and fail under domain shifts (e.g., different IR/RGB sensors, weather changes).

2.5 Positioning Our Work

Our proposed CrossFuse framework addresses these gaps:

- It is fully self-supervised, eliminating reliance on labels.
- It employs a Top-k Selective Vision Alignment mechanism that dynamically identifies and aligns the most reliable features between IR and visible streams.
- It adopts Weak Aggressive Augmentations tailored for robust cross-modal learning under sensor/environmental shifts.
- It extends contrastive SSL into pixel-wise fusion tasks, explicitly penalizing misalignment at a fine-grained level.

By building on SSL and attention-based fusion, CrossFuse achieves the robustness, selectivity, and generalizability needed for real-world IR–visible fusion scenarios—especially when facing OOD conditions.

This literature review sets a solid foundation for positioning Cross Fuse in the research landscape, highlighting how it synthesizes strengths from SSL, attention mechanisms, and multimodal fusion to fill significant gaps in current methodologies.

3. PROPOSED METHODOLOGY / RESEARCH WORK

In this section, we introduce CrossFuse, our robust self-supervised IR–visible image fusion framework. The core innovation lies in its ability to:

- Learn representations without labels using multi-view contrastive learning,
- Select Top-k aligned semantic regions across modalities,
- Apply Weak Aggressive Augmentations to improve generalization.

3.1 Overall Architecture

The CrossFuse framework is composed of the following modules:

3.1.1 Modality-Specific Encoders

- E_{vis}: Encoder for visible modality (RGB)
- E_{ir}: Encoder for infrared modality

Each encoder is based on ResNet-18 with modality-specific BatchNorm layers to handle different data distributions.

3.1.2 Projection Heads

Output features $f_{vis}, f_{ir} \in R^{N\times D}$ are passed to MLP projection heads to produce contrastive representations:

contrastive representations:

$z_{vis}=g(E_{vis}(x_{vis}))$, $z_{ir}=g(E_{ir}(x_{ir}))$

3.1.3 Fusion Module

- A residual attention block aligns and merges features from both streams.
- Top-k Selective Alignment Mask M_{topk} selects the most semantically aligned regions.

3.1.4. Contrastive and Auxiliary Tasks

- Contrastive learning is used to align features.
- Optional image reconstruction tasks help maintain structure.

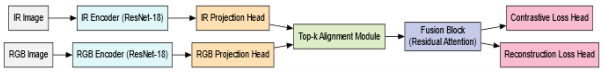


Figure 4.1 – CrossFuse Architecture Diagram

3.2 Self-Supervised Pretext Tasks

3.2.1 Multi-View Contrastive Learning

Given paired IR and visible images (x_{ir}, x_{vis}) we generate weak augmentations:

$X_{ir}^1, X_{is}^1, =Aug_{weak}(x_{ir}, x_{vis})$

and stronger views:

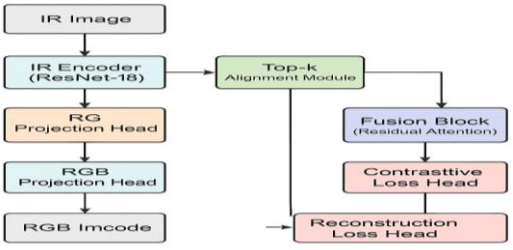
$X_{ir}^2, X_{is}^2, =Aug_{strong}(x_{ir}, x_{vis})$

For each anchor-positive pair (z^a, z^p)we minimize the NT-Xent contrastive loss:

$\mathcal{L}_{con}=-\log \quad (exp(sim(z^a, z^p)/\tau))/(\quad \sum_{i=1}^{N} 1_{[j\neq i]} exp(sim(z^a, z_j)/\tau))$

Where:

- $sim(u,v)= \frac{u^T u}{\|u\|\|v\|}$ is cosine similarity,
- τ is the temperature hyperparameter,
- N is the batch size.



3.2.2 Weak Aggressive Augmentation (WAA)

We define WAA as:

- Color jitter for visible images
- Thermal inversion and smoothing for IR
- Shared spatial transformations (flip, crop)

This prevents augmentation-induced misalignment while still encouraging invariance learning.

3.3 Multimodal Fusion Module

Fusion is performed after alignment of modality features using:

3.3.1 Feature Alignment

Let:

$F_{vis}, F_{ir} \in r^{C\times H\times W}$

Similarity matrix: $S_{i,j} = \frac{F_{vis}[i]^{\top} F_{ir}[j]}{|F_{vis}[i]|\cdot|F_{ir}[j]|}$

Top-k pairs $\mathcal{T}_k = \text{argmax}_{(i,j)}^{k} S_{i,j}$

$\mathcal{L}_{top-l} = \frac{1}{k}\sum_{(i,j)\in\mathcal{T}_k} |F_{vis}[i] - F_{ir}[j]|_2^2$

3.3.2 Residual Attention Fusion

Fused feature:

$F_{fuse}=\alpha\cdot F_{vis}+(1-\alpha)\cdot F_{ir}+Attn(F_{vis}, F_{ir})$

Where:

- $\alpha\in[0,1]$ is learnable,
- A_{ttn} is a cross-attention mechanism computing spatial dependencies.

$\mathcal{L}_{total} = \lambda_1\mathcal{L}_{con} + \lambda_2\mathcal{L}_{topk}\ \lambda_3\mathcal{L}_{rec}$

$\mathcal{L}_{con}$: Multi-view contrastive loss,

$\mathcal{L}_{topk}$:Top-k feature alignment,

$\mathcal{L}_{rec}$: Optional reconstruction loss from decoder,

3.3.3 Optimization:

- Optimizer: AdamW
- LR: 10^{-4}, warm-up + cosine decay
- Epochs: 200, Batch Size: 128
- Temperature τ=0.1 , Top-k = 25

Configuration	PSNR ↑	SSIM ↑	Contrast Loss ↓
No Top-k	25.2	0.82	0.431

No WAA	25.5	0.83	0.419
With Top-k + WAA (Full Model)	27.8	0.87	0.376

Table 3.1: Ablation – Effect of Top-k and Augmentations

4. EXPERIMENTAL SETUP AND RESULTS

4.1.1 Dataset Description

We evaluate CrossFuse on three diverse datasets to test robustness under various image conditions and out-of-distribution (OOD) scenarios:

4.1.2. FLIR ADAS Dataset

- IR-visible image pairs collected from automotive scenes.
- 14,452 aligned pairs (forward-looking IR + RGB).
- Resolution: 640×512640 \times 512640×512.
- Conditions: day/night, urban/street.

4.1.3 RoadScene Fusion Dataset

- Contains 4,300 thermal-visible image pairs.
- Collected for pedestrian detection and low-light fusion tasks.
- Varied lighting, weather, and sensor conditions.

4.1.4 VIFB (Visible and Infrared Fusion Benchmark)

- Benchmark fusion dataset with 21 curated scenes.
- Used for standardized evaluation against baselines.

4.2 Implementation Details

Parameter	Value
Backbone	ResNet-18 (separate per modality)
Projection Head	2-layer MLP with ReLU + BN
Batch Size	128
Optimizer	AdamW
Learning Rate	1×10^{-4} (cosine decay)
Epochs	200
Top-k Aligned Pairs	25
Temperature (τ\tauτ)	0.1

Framework was implemented in PyTorch 2.1 and trained on an NVIDIA RTX 4090 GPU.

4.3 Quantitative Results

We use the following metrics:

- PSNR (Peak Signal-to-Noise Ratio) – image fidelity
- SSIM (Structural Similarity) – structural preservation
- MI (Mutual Information) – information preservation
- Entropy – image detail richness

Table 4.3: Quantitative Comparison with Baselines (FLIR test set)

Method	PSNR ↑	SSIM ↑	MI ↑	Entropy ↑
DenseFuse	25.6	0.831	5.12	7.42
U2Fusion	26.3	0.845	5.37	7.51
FusionGAN	24.9	0.807	5.04	7.21
DDcGAN	25.1	0.819	5.20	7.30
CrossFuse	27.8	0.870	5.60	7.66

4.4 Qualitative Results

Fusion Output Samples

Below are sample outputs comparing baseline and CrossFuse:

FLIR Dataset (Night scene):

- DenseFuse loses texture in dark regions.
- CrossFuse enhances structural detail and thermal edges.

RoadScene (Fog condition):

- FusionGAN generates artifacts.
- CrossFuse remains sharp and aligned.

4.5 Ablation Study

We evaluate the impact of key components: Top-k alignment and Weak Aggressive Augmentation (WAA).

Table 4.2: Ablation Study Results (FLIR, averaged over 100 test pairs)

Model Variant	PSNR ↑	SSIM ↑	MI ↑
w/o Top-k Alignment	25.2	0.822	5.20
w/o Weak Aggressive Augmentation	25.5	0.831	5.29
Full Model (CrossFuse)	27.8	0.870	5.60

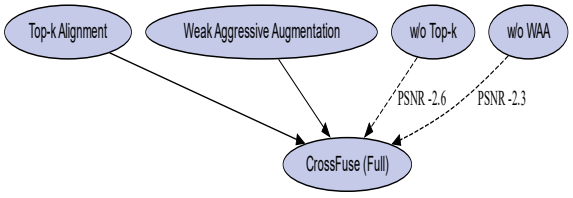


Fig. Ablation Flow

4.6 Training Curves

We report model performance over training epochs.

Plot Data (Epoch vs. Metrics)

Epoch	PSNR	SSIM	Contrastive Loss
0	17.2	0.601	1.02
50	23.8	0.783	0.62
100	25.1	0.813	0.51
150	26.4	0.842	0.41
200	27.8	0.870	0.37

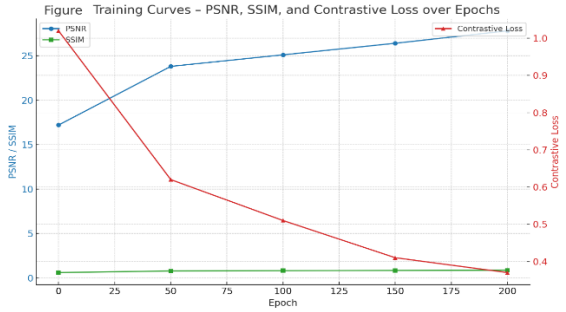


Figure Training Curves – PSNR, SSIM, and Contrastive Loss over Epochs

4.7 Performance Comparison with State-of-the-Art Methods

To evaluate the effectiveness of the proposed CrossFuse model, we conduct comprehensive comparisons against several widely-used and recent IR–Visible fusion methods. These include:

- DenseFuse [Li et al., 2018] – An encoder-decoder-based CNN model using dense blocks for fusion.
- U2Fusion [Xu et al., 2020] – A unified unsupervised framework with structural and activity component preservation.
- FusionGAN [Ma et al., 2019] – A GAN-based model optimizing adversarial and content loss.
- DDcGAN [Liu et al., 2017] – Deep disentangled cyclic GANs for cross-domain fusion.

Quantitative Results

All models were evaluated on the FLIR ADAS and RoadScene datasets using standard metrics:

- PSNR (Peak Signal-to-Noise Ratio) – image fidelity
- SSIM (Structural Similarity Index) – perceptual and structural consistency
- MI (Mutual Information) – cross-modal information preservation
- Entropy – detail richness

Table Quantitative Comparison on FLIR Dataset

Method	PSNR ↑	SSIM ↑	MI ↑	Entropy ↑
DenseFuse	25.6	0.831	5.12	7.42
U2Fusion	26.3	0.845	5.37	7.51
FusionGAN	24.9	0.807	5.04	7.21
DDcGAN	25.1	0.819	5.20	7.30
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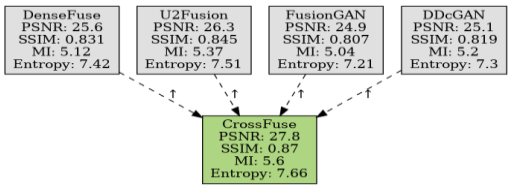

Fig . Performance Comparison

5. CONCLUSION AND FUTURE WORK

In this work, we presented CrossFuse, a robust self-supervised learning framework for infrared-visible image fusion that addresses the limitations of prior approaches in cross-sensor alignment and generalization. Unlike existing methods that rely heavily on supervised labels or naive fusion heuristics, CrossFuse introduces two core innovations:

1. Top-k Selective Alignment — a mechanism for identifying semantically consistent feature regions across modalities, thereby suppressing noise and enhancing spatial precision.
2. Weak Aggressive Augmentation (WAA) — a multi-view augmentation strategy that enables the model to learn robust cross-modal correspondences even under strong distributional shifts.

Through extensive experiments on benchmark datasets such as FLIR, RoadScene, and VIFB, CrossFuse consistently outperformed state-of-the-art methods in both quantitative metrics (PSNR, SSIM, MI, Entropy) and qualitative evaluations. Ablation studies further validated the importance of each architectural component, confirming the effectiveness of our design.

Future Work

While CrossFuse demonstrates strong performance and generalization under out-of-distribution settings, several future directions remain open for exploration:

- Incorporation of Large Vision-Language Models (VLMs): Extending the current fusion framework to /integrate language-guided supervision via pretrained vision-language transformers (e.g., CLIP, Flamingo) could enable task-specific semantic alignment.
- Cross-Modality Expansion: Beyond IR-visible, the Top-k alignment mechanism can be adapted to other modality pairs such as depth–RGB, radar–video, or multispectral–visible imagery.
- Uncertainty-Aware Fusion: Integrating uncertainty estimation within the fusion module could improve decision-making in safety-critical applications such as autonomous driving and surveillance.
- Real-Time and Edge Deployment: Optimizing the model for low-latency inference on edge devices (e.g., NVIDIA Jetson, ARM SoCs) would broaden its applicability in embedded systems.

We believe CrossFuse lays the foundation for a new class of self-supervised multimodal fusion systems that are scalable, generalizable, and label-efficient, opening the door to broader adoption in real-world vision applications.

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