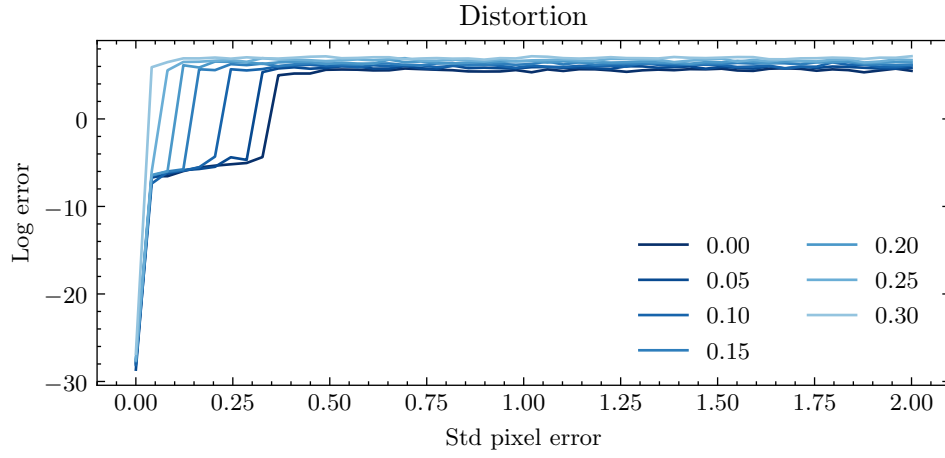# Supplement: Solving the Plane-Sphere Ambiguity in Top-Down Structure-from-Motion
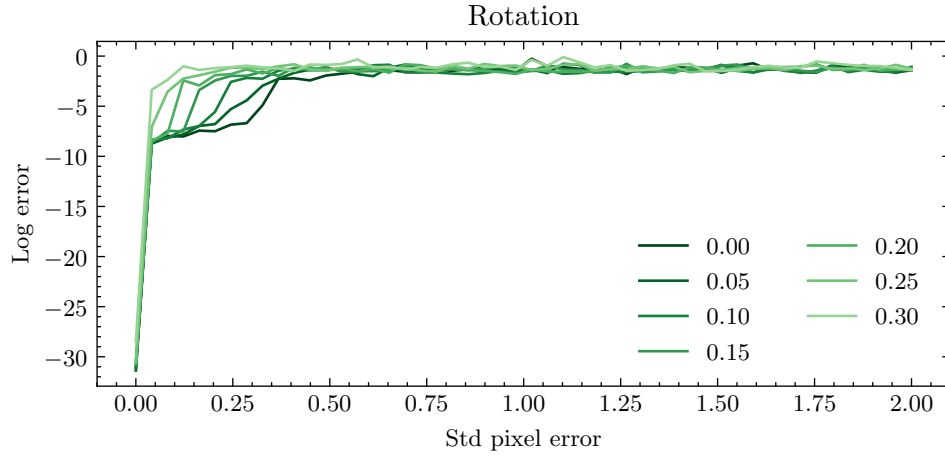
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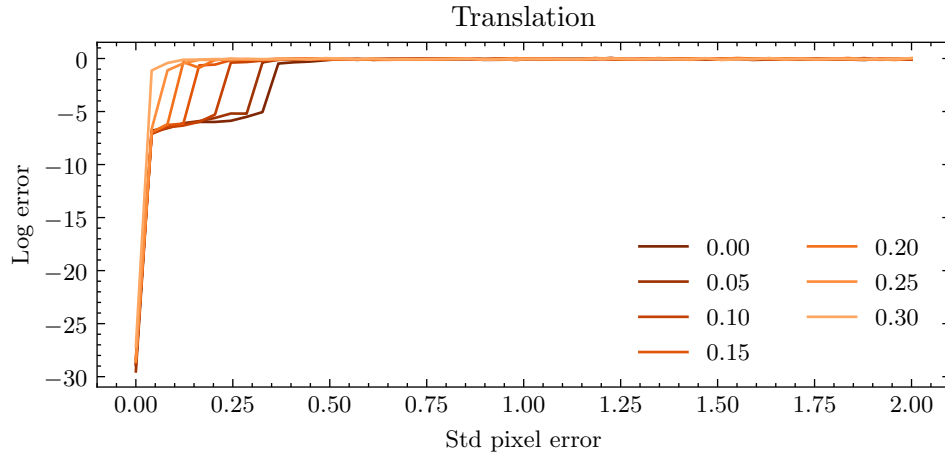University of Münster, Germany

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(a) Errors for distortion.

(b) Errors for rotation.

(c) Errors for translation.

Figure S1: Synthetic dataset: Estimation errors for different outlier ratios.. For the synthetic dataset described in the main text, the median errors for increasing pixel noise are plotted. Pixel noise is quantified using the standard deviation of a Gaussian distribution. Distortion, translation and rotation errors are again measured using the absolute difference, $L2$-norm and absolute angle difference respectively.