S-TREK: Sequential Translation and Rotation Equivariant Keypoints for local feature extraction

Emanuele Santellani *, Christian Sormann *, Mattia Rossi [†], Andreas Kuhn [†], Friedrich Fraundorfer * * Graz University of Technology, [†] Stuttgart Laboratory 1, SSS-EU, Sony Europe B.V.

* name.surname@icg.tugraz.at, [†] name.surname@sony.com

1. Supplementary material

We include additional qualitative comparisons on *Image Matching Benchmark* [2] and our rotated versions with all the tested methods in Figure 1, Figure 2 and Figure 3.

In Figure 4 we include an extended version of the main

paper figure which shows the detector heatmaps evolution during training. We include the additional 32 and 96 *Peaky* loss window sizes and our training framework run using 100 serial samples.



Figure 1: Qualitative comparison with state-of-the-art feature extraction methods on the Image Matching Benchmark [2] (top) and on our $\pm 20^{\circ}$ and $\pm 45^{\circ}$ rotated version of it. RANSAC inlier matches are color coded from green to yellow, representing reprojection errors equal to zero and 5px, respectively; the outlier matches are in red.



Figure 2: Qualitative comparison with state-of-the-art feature extraction methods on the Image Matching Benchmark [2] (top) and on our $\pm 20^{\circ}$ and $\pm 45^{\circ}$ rotated version of it. RANSAC inlier matches are color coded from green to yellow, representing reprojection errors equal to zero and 5px, respectively; the outlier matches are in red.



Figure 3: Qualitative comparison with state-of-the-art feature extraction methods on the Image Matching Benchmark [2] (top) and on our $\pm 20^{\circ}$ and $\pm 45^{\circ}$ rotated version of it. RANSAC inlier matches are color coded from green to yellow, representing reprojection errors equal to zero and 5px, respectively; the outlier matches are in red.



Figure 4: Visual comparison between different training methods on the validation set of the synthetic lines dataset. Last row: input images and detected keypoints (Green - repeatable, Red - non repeatable, Yellow - non overlapping). First three rows: detector heatmaps evolution during training. Our training framework excels at finding the repeatable points without any direct supervision.

References

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