Unsupervised Deep Epipolar Flow for Stationary or Dynamic Scenes –Supplemental Material

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Abstract

In this supplemental material, we provide more qualitative results of optical flow estimation on the KITTI VO dataset. Furthermore, on stationary scenes, we compare our method with the conventional RANSAC method [2] in fundamental matrix estimation on a subset of the KITTI 2012 training set.

1. Fundamental Matrix Recovery

Our method has the potential to recover a fundamental matrix for a stationary scene. To evaluate our recovered fundamental matrix, we select several stationary scenes from the KITTI 2012 training dataset and compare our results with the fundamental matrices computed from ground truth optical flows and the fundamental matrices computed from sparse feature correspondences. To compute fundamental matrix from ground truth optical flow, we first convert a ground truth flow into matching point pairs and then use the normalized eight-point algorithm to compute the corresponding fundamental matrix. For sparse feature correspondences based fundamental matrix, we detect SURF [1] features and perform feature matching. The fundamental matrix is computed with RANSAC + normalized eight-point algorithm. We use MATLAB's inbuilt function *estimateFundamentalMatrix*.

In Fig. 1, we illustrate our fundamental matrix estimation performance under these two conditions. We report our results based on the Gold Standard Method [3]. The left column visualizes the epipolar line estimation from a small forward movement while the right one from a large turn. Our baseline model, which only uses image warping constraint, shows competitive performance in small motions but has relatively large errors in large motions. Our methods that enforce the epipolar constraint, *i.e.*, Our-F, Our-low-rank and Our-sub, share similar performance, with Our-sub achieving the lowest re-projection error. Table 1 provides quantitative results, comparing our recovered **F** against the result of RANSAC [2].

References

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