Supplementery Material for "What Makes Good Synthetic Training Data for Learning Disparity and Optical Flow Estimation?"

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This document contains supplementary material for "What Makes Good Synthetic Training Data for Learning Disparity and Optical Flow Estimation?". The supplementary material consists of samples (first and second frame) from the optical flow training datasets used in the main paper. Most datasets were created specifically for this work, but we also used the existing Flying Chairs from Dosovitskiy et al (2015) and Flying Things 3D from Mayer et al (2016).

References

Dosovitskiy A, Fischer P, Ilg E, Häusser P, Hazırbaş C, Golkov V, van der Smagt P, Cremers D, Brox T (2015) FlowNet: Learning optical flow with convolutional networks. In: IEEE International Conference on Computer Vision (ICCV) 1, 4

Mayer N, Ilg E, Häusser P, Fischer P, Cremers D, Dosovitskiy A, Brox T (2016) A large dataset to train convolutional networks for disparity, optical flow, and scene flow estimation. In: IEEE Conference on Computer Vision and Pattern Recognition (CVPR) 1, 4

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Fig. 1 Dataset gallery 1/4: Boxes, Polygons and Ellipses variants as used in Sec. 5.2.1 in the main paper (see also Table 3 ibid.)

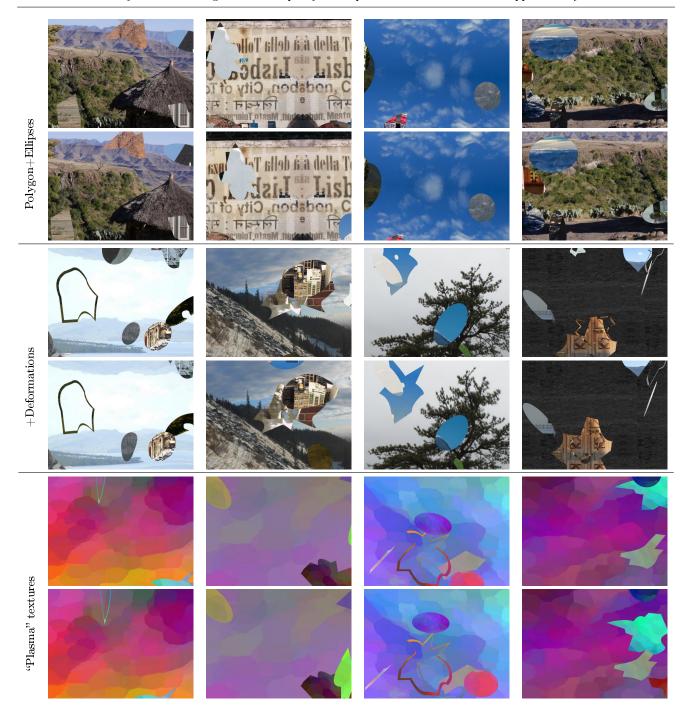


Fig. 2 Dataset gallery 2/4: Polygons+Ellipses and Polygons+Ellipses+Deformations variants as used in Sec. 5.2.1 in the main paper (see also Table 3 *ibid.*); "Plasma" textures as used in Sec. 5.2.2 *ibid.*

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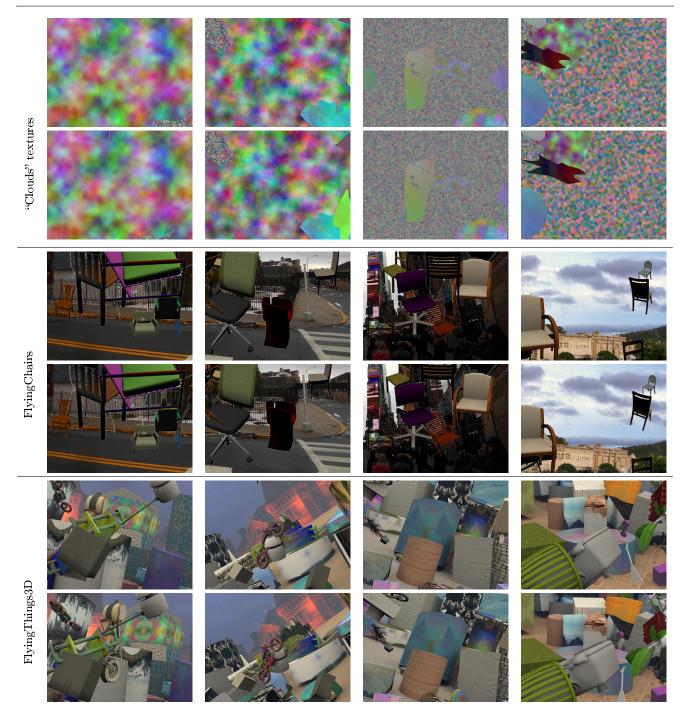
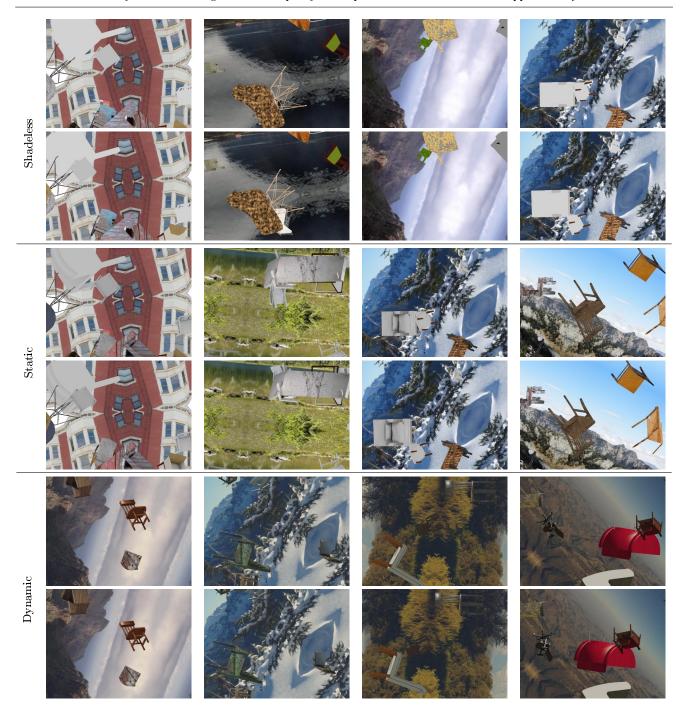


Fig. 3 Dataset gallery 3/4: "Clouds" textures as used in Sec. 5.2.2 in the main paper; FlyingChairs from Dosovitskiy et al (2015); FlyingThings3D (cropped to the same 4:3 aspect ratio as the other datasets for display purposes) from Mayer et al (2016).



 $\textbf{Fig. 4 Dataset gallery 4/4:} \ \textbf{Shadeless}, \ \textbf{static and dynamic lighting variants as used in Sec. 5.2.4 in the main paper.}$