

# Charge: A Comprehensive Benchmark and Dataset for Dynamic Novel View Synthesis

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Figure 1. Charge is a new dataset for dynamic novel view synthesis characterised by high-quality renderings and rich annotations. The example includes left-to-right: object segmentation, normals, RGB, depth, and optical flow.

## Abstract

*This paper presents a new dynamic dataset for novel view synthesis, generated from a high-quality, animated film with stunning realism and intricate detail. Our dataset captures a variety of dynamic scenes, complete with detailed textures, lighting, and motion, making it ideal for training and evaluating 4D scene reconstruction and novel view generation models. In addition to high-fidelity RGB images, we provide multiple complementary modalities, including depth, surface normals, object segmentation and optical flow, enabling a deeper understanding of scene geometry and motion. The dataset is organised into three distinct benchmarking scenarios: a dense multi-view camera setup, a sparse camera arrangement, and monocular video sequences, enabling a wide range of experimentation and comparison across varying levels of data sparsity. With its combination of visual richness, high-quality annotations, and diverse experimental setups, this dataset offers a unique resource for pushing the boundaries of view synthesis and 3D vision. The dataset is available at <https://charge-benchmark.github.io/>.*

## 1. Introduction

Access and availability of high-quality, large-scale datasets for the training and evaluation of algorithms is arguably one of the main engines for progress and innovation in computer vision. With the advent of digital photography and the internet, an abundance of images readily available has been a good example of this: it unlocked unprecedented development and breakthroughs in a number of tasks, *e.g.* image classification, low-level vision, specially when leveraging forms of self-supervision that alleviate for the need of costly manual data annotation.

Recently, the seminal Neural Radiance Fields (NeRFs) by Mildenhall *et al.* [20] reconstructs the 3D opacity and radiance of a scene by fitting an implicit representation supervised via differentiable volumetric rendering and photometric loss on a dense set of posed 2D images. NeRFs have an undeniable appeal due to the simplicity of their capture, *i.e.* coupled with *off-the-shelf* Structure-from-Motion (SfM) camera pose estimators such as COLMAP [26], they can reconstruct 3D from a handful of 2D images. Such paradigm is exciting as it can potentially overcome some of the hardware bottlenecks around capturing 3D data at scale thanks to its reliance on a single camera to obtain 2D im-

Table 1. A summary and comparison of datasets used in dynamic novel view synthesis. The top section includes datasets used for multi-view evaluation whereas the middle section focuses on monocular evaluation data.  $\dagger$  - 2 camera rig with alternating frames assigned to training and test trajectory.

Dataset	Dense	Sparse	Mono	Depth	FPS	# seq	# train cams	# test cams	# frames
Neural 3D Video [14]	✓	✗	✗	✗	30	6	20	1	56 700
Technicolor [25]	✓	✗	✗	✗	30	5	15	1	25 696
Google Immersive [3]	✓	✗	✗	✗	30	7	45	1	157 320
Nvidia Dynamic Scene [33]	✓	✗	✗	✓	60	8	1	11	2 304
D-NeRF [24]	✗	✗	✓	✗	60	8	1	1	1 410
Nerfies [22]	✗	✗	✓	✗	5	4	1 $\dagger$	1 $\dagger$	1 680
HyperNeRF [23]	✗	✗	✓	✗	15	17	1 $\dagger$	1 $\dagger$	2 152
DyCheck [7]	✗	✗	✓	✓	60	7+7	1	2/0	8 746
Ours	✓	✓	✓	✓	96	8	25+9+4	16+10+16	185 600

agery and SfM for the camera poses.

Differentiable rendering has received significant number of follow-up works, *e.g.* dense, sparse, varying appearance. Most of these assume static scenes and fixed radiance fields. Extending static to dynamic scene reconstruction is challenging. There has been recent interest in addressing this problem, with early paradigms extending NeRF [23, 24] or 3DGS [17, 31, 36] with temporal deformation.

Capturing datasets for novel view synthesis of dynamic scenes is inherently difficult. As opposed to static scenes, camera pose estimation on dynamic scenes is a challenging and largely unsolved problem, *i.e.* movement in the scene can introduce matching errors that then degrade the estimated camera poses. Furthermore, due to low image sampling rates (*e.g.* 24 fps), *soft* or inaccurate camera synchronisation can in turn impact the camera pose and reconstruction accuracy. In practice, this means complex, hardware-synchronised multi-camera systems are needed to obtain multiple views of the scene [15, 19]. Such connected rigs impose constraints on the physical distribution of the cameras, restrict the scene diversity due to the limitations on physical spaces where they can be deployed (*i.e.* indoors, volumetric studios), and ultimately can not be pragmatically moved within the scene (in part due to weight, fragility and build, but also because of potential problems with camera calibration). The need for testing views results in a reduction of the number of training views available, a trade-off that often result in poor camera sampling for evaluation. For approaches where separated, non-synchronised cameras are used for the testing views [7], problems can arise in the camera calibration in dynamic scenes. This, coupled with the lack of precise temporal frame alignment, degrades the ability to accurately evaluate the performance of 4D reconstruction methods.

Given the current technical limitations to capture dynamic 3D data, we find inspiration on the *MPI Sintel* dataset by Butler *et al.* [4]. In our work, we present a novel high-resolution, dynamic dataset for NVS with rich modalities

(RGB, depth, normals, segmentation), and overcomplete training and testing camera coverage that addresses open challenges of dynamic 3D reconstruction. The dataset is arranged for different dynamic reconstruction set-ups, namely dense input, sparse input, and monocular input (with varying configurations of the camera trajectories, *e.g.* fast/slow, spline/random). We show a visualisation of the modalities in Figure 1, and an overview of the dataset composition in Figure 2. This dataset is generated from the high-quality animated movie Charge [8] including rich scene compositions and a variety of dynamic content. The synthetic nature of the dataset allows us to introduce a large-scale dataset and benchmark not viable to be collected in the real world due to capture cost, physical limitations around camera placements, and ultimately accurate pose estimation. We summarise our contributions as follows:

1. We introduce a new synthetic dataset - Charge - for dynamic novel view synthesis. It is characterised by high visual quality, it outscales all other available datasets in the number of provided images, and it provides rich annotations offering a variety of additional modalities.
2. We unify all relevant 4D reconstruction setups - Dense, Sparse, Mono, and provide benchmarking for all.
3. We perform an extensive evaluation of state-of-the-art reconstruction methods and analyse the results emphasising the importance of the benchmark we propose.

## 2. Related Work

Advances in novel view synthesis include the introduction of two seminal reconstruction paradigms, namely Neural Radiance Fields [20] and 3D Gaussian Splatting [10]. These developments in static scene reconstruction were quickly followed by several works on dynamic content.

**Dynamic Reconstruction:** NeRF-based methods for video reconstruction include D-NeRF [24], StreamRF [13], HexPlane [5], K-Planes [6], Tensor4D [27], MixVoxels [29]. Representative monocular approaches include NSFF [16], Nerfies [22], HyperNeRF [23], DyCheck [7]. Similarly,

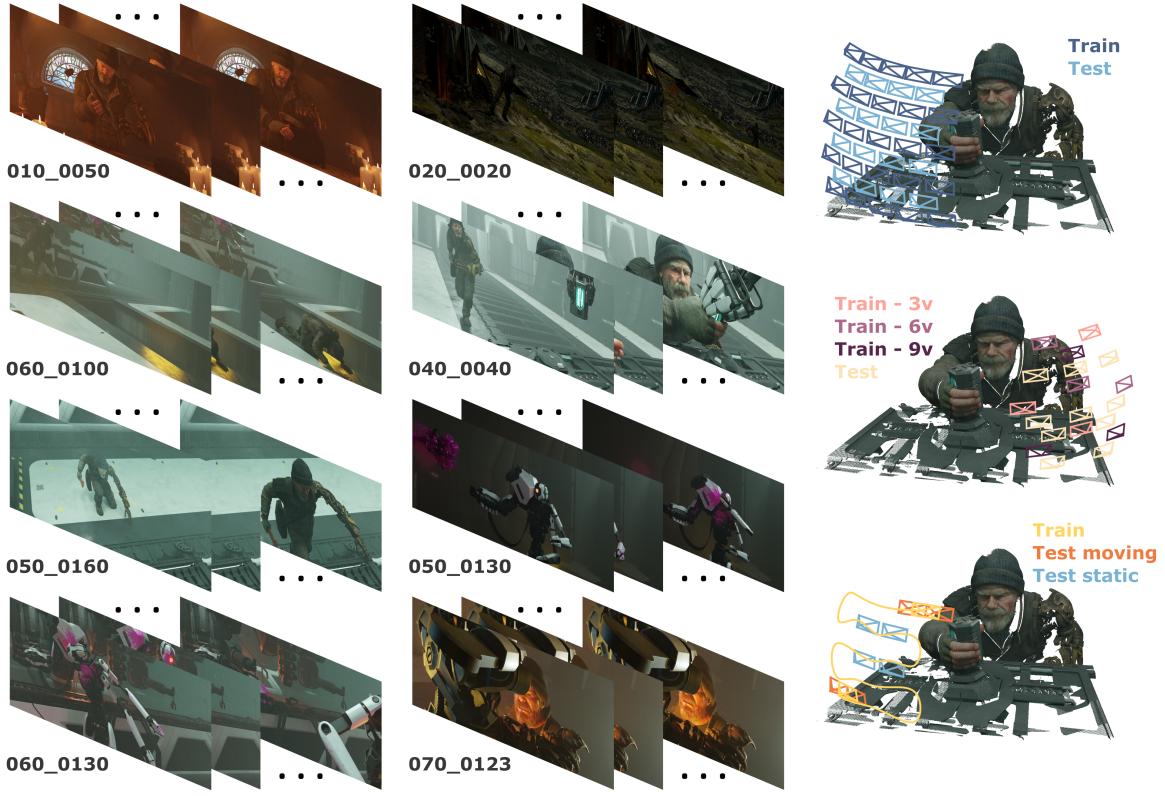


Figure 2. An overview of the Charge dataset. The left side presents a selection of frames from all the animations. On the right side, 3 setups included in the dataset are presented: Dense, Sparse, and Mono. Cameras allocation and sample movement path for monocular trajectory are overlayed on the section of the point cloud corresponding to scene 040\_0040.

Gaussian Splatting developments enabled research on dynamic novel view synthesis. Multi-view videos were reconstructed by: GaussianFlow [18], 4DGS [31], STG [17], MotionGS [36], SWinGS [28], Ex4DGS [11]. The most recent advances in Gaussian Splatting include monocular video reconstructions by works such as Deformable 3D Gaussians [32], SC-GS [9], or MoSca [12].

**Datasets:** Current evaluation of multi-view dynamic novel view synthesis is based on a handful of datasets summarised in Table 1. This includes a selection of real-world captured data. Neural 3D Video [14] introduces a series of indoor cooking scenes captured with a static rig of GoPro cameras. Similarly, the Technicolor dataset [25] provides several scenes captured with a synchronized rig of  $4 \times 4$  cameras. The shortcoming of the aforementioned two datasets is the reduced amount of dynamic content (*e.g.* cooking action occupies only a small middle region of the videos), and relatively slow motions. Additionally, those datasets evaluate the performance of the proposed approach only on a 1 camera subselected from the whole rig. Google Immersive [3] provides dynamic videos captured with a spherical rig of outward-facing cameras and suffers from heavy fish-eye distortions and very low overlap between views. DiVa-360 [19] captures a set of objects and hand-object in-

teractions with a 360° setup. Monocular video datasets include *e.g.* Nvidia Dynamic Scene [33] which introduces sequences captured by a rig of 12 cameras subsampling alternating views to create a monocular trajectory (however aggressively temporally subsampled). Nerfies [22] and HyperNeRF [23] introduce a monocular video by capturing action with two cameras and alternating their frames in the input and test sequences. These datasets suffer from highly unrealistic motion due to teleporting cameras creating in this way pseudo-multi-view capture. This is characterised as a high effective multi-view factor in DyCheck [7], which introduces a new monocular capture with 2 static cameras for evaluation. However, it suffers from an imperfect set of camera poses for the training trajectory. A better set of camera poses can be seen in DTU [1] dataset which was captured with a camera mounted on a robotic arm. It is broadly used in novel view synthesis evaluation in dense and sparse setups. However, it provides only static scenes. Similarly, Sparse Neural Rendering Dataset [21] provides a DTU-like setup but in a synthetic version, and thus is also static and present a single object per scene (no complex scenes). D-NeRF [24] is a synthetic dataset of dynamic content. It captures lower-quality subject assets on a white background from a set of cameras placed on a dome. Further, it creates

Table 2. Percentage of dynamic content in various datasets.

Data	Charge	DyCheck	Neural 3D	Technicolor
Dynamic	25.1 %	12.6 %	10.9 %	9.7 %

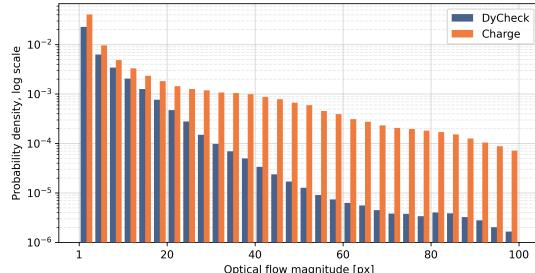


Figure 3. Optical flow histogram for DyCheck and Charge.

a monocular input sequence by sampling consecutive cameras (suffering from teleporting-related issues). In contrast, Charge provides high-quality renderings of rich sequences with carefully designed setups for dense and sparse multi-view, and monocular captures.

In Table 2, we show a breakdown of dynamic content in current datasets by presenting a percentage of pixels occupied by dynamic objects. Notably, frames in Charge are occupied on average by twice the amount of dynamic parts than the closest competitor. Similarly, in Figure 3 we show histograms of optical flow magnitude for our Charge in comparison to DyCheck [7] for their respective dynamic regions. Charge has higher density of dynamic pixels, and has better coverage across the diverse magnitudes, with special advantages on large motions.

### 3. The Charge Dataset

In this work we introduce a new dataset for dynamic novel view synthesis. In pursue of high-quality data, we explored a scene of animated movies created in the rendering software Blender [2]. Specifically, we focus on the latest release of Charge, a short movie set in a dystopian world, created to showcase Blender’s photorealistic rendering capabilities.

#### 3.1. Dataset Creation

We utilise production shots (short scenes provided with 3D assets) from the Charge movie to create our dataset. For each such scene a composition with animation, lighting, and a library of items is available. We processed all 8 available scenes for Charge of which examples can be seen in Figure 2 (left). For every scene, we manually picked places for cameras for the best capture and visibility of the scene after spanning the whole rig. Additionally, we removed the original rendering pipeline due to postprocessing effects that may degrade the 3D consistency of the capture. Instead, we replace the rendering pipeline with direct rendering from the camera, and we add rendering of additional modalities (such as depth, or normals). We temporally upsample this

action-heavy movie developed in 24 fps via subsampling at the animation level by a factor of  $\times 4$ .

#### 3.2. Camera Setups

The Charge dataset provides the unique benchmarking feature of having various camera setups corresponding to commonly tackled novel view synthesis problems within the exact same scenes, namely: Dense, Sparse, and Mono. Commonly used camera setups include the use of coplanar capture or dome capture. Inspired by that, we decided to place the cameras on the section of the sphere, such that scenes are mostly forward-facing (similar to most real-world captures), yet offer the benefits of changing perspective. To this end, we manually adjust the position of the rig and the radius of the aforementioned sphere for each scene.

**Dense** setup consists of 25 training cameras and 16 testing cameras (see Fig. 2 top right). This offers a setup similar to Neural 3D Video [14] or Technicolor [25]. Those works, limited by the constraints of the real world (high capture cost), offer only one camera for testing. We provide a rig of 16 testing cameras allowing for more thorough evaluation.

**Sparse** setup follows a common practise in literature (*e.g.* pixelNeRF [34]) and we provide training scenarios including 3, 6, or 9 training cameras, accompanied by 10 testing views (see Fig. 2 middle right). Note that the sparse setup covers the scenes from a different perspective instead of simply subsampling the training cameras. This increases the diversity of our dataset and opens up new areas of research and exploration when performing distant novel view synthesis, *i.e.* with an emphasis on view extrapolation as opposed to interpolation.

**Mono** setup introduces 4 different trajectories of the monocular camera. We aim to reproduce in this setup camera motions that are viable with a handheld device. As characterised by DyCheck, a monocular capture should not exhibit a high effective multiview factor (*e.g.* teleporting or extremely fast camera). To this end, based on empirical experimentation with the use of a phone camera and a target captured from around 1 – 2m, we estimate that the reasonable velocity of a capture device lies around the range of 15–50cm/s. Therefore, we introduce *Fast* and *Slow* monocular trajectories corresponding roughly to the upper and lower bounds of the measured values. Similarly, we propose that the capture may deliberately try to cover a wider perspective or be less regularised. Hence, we suggest two qualities of the camera trajectory: *Spline* - constrained to a spline curve spanning the majority of corresponding training camera positions, and *Random Walk* - randomly generated direction for every time step with a smoothing factor. This results in the following training scenarios: *SplineFast*, *SplineSlow*, *RandomWalkFast*, *RandomWalkSlow*. Further, monocular reconstruction encompasses many downstream goals, such as stabilisation, or spatial video (stereo pair syn-

Table 3. Quantitative evaluation results of Charge dataset - Dense and Mono setups, -D denotes metrics on dynamic-only areas, -S static only and  $FOV_O$  quantifies the field-of-view overlap between testing and training views (*i.e.* harder when lower). Best performer.

Method	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	$FOV_O$
<b>Dense</b>								
4DGs [31]	28.94	26.84	<u>31.85</u>	0.881	0.848	0.231	0.307	0.70
STG [17]	29.29	28.15	<u>31.33</u>	0.886	<u>0.866</u>	0.193	<u>0.263</u>	0.70
Ex4DGs [11]	<u>29.75</u>	<u>28.57</u>	31.57	<u>0.893</u>	0.863	<u>0.187</u>	<u>0.264</u>	0.70
<b>Mono - Spline Fast</b>								
4DGs [31]	24.85	22.69	<u>27.25</u>	0.840	0.794	0.264	0.352	0.42
D-3DGs [32]	<u>24.88</u>	22.91	<u>27.24</u>	<u>0.869</u>	0.807	<u>0.201</u>	0.295	0.42
SC-GS [9]	23.97	<u>23.57</u>	25.89	0.847	0.798	<u>0.217</u>	<u>0.291</u>	0.42
MoSca [12]	23.39	22.84	24.10	0.853	<u>0.817</u>	0.255	0.320	0.42
<b>Mono - Spline Slow</b>								
4DGs [31]	<u>24.18</u>	21.95	<u>26.65</u>	0.834	0.787	0.266	0.360	0.41
D-3DGs [32]	<u>24.18</u>	22.53	<u>26.15</u>	<u>0.858</u>	0.794	<u>0.203</u>	<u>0.290</u>	0.41
SC-GS [9]	23.29	22.54	25.15	0.843	0.786	0.225	0.304	0.41
MoSca [12]	23.45	22.83	24.63	0.856	<u>0.815</u>	0.244	0.323	0.41
<b>Mono - Random Walk Fast</b>								
4DGs [31]	<u>24.78</u>	22.79	<u>26.81</u>	0.835	0.790	0.267	0.359	0.41
D-3DGs [32]	24.34	22.55	<u>26.24</u>	0.852	0.789	<u>0.217</u>	<u>0.309</u>	0.41
SC-GS [9]	22.90	<u>23.04</u>	24.22	0.822	0.775	0.243	<u>0.314</u>	0.41
MoSca [12]	23.82	22.77	25.09	<u>0.857</u>	<u>0.817</u>	0.251	0.325	0.41
<b>Mono - Random Walk Slow</b>								
4DGs [31]	23.38	21.68	<u>25.64</u>	0.818	0.771	0.277	0.370	0.38
D-3DGs [32]	22.85	21.61	<u>24.76</u>	0.829	0.762	<u>0.227</u>	0.318	0.38
SC-GS [9]	21.86	21.73	<u>23.51</u>	0.811	0.762	0.244	0.318	0.38
MoSca [12]	<u>24.29</u>	<u>23.61</u>	25.23	<u>0.871</u>	<u>0.829</u>	0.229	<u>0.306</u>	0.38

thesis). Thus, we propose to test each of these trajectories with 4 static cameras chosen from the set of Dense testing cameras (allowing for direct comparison), and 4 cameras defined relative to the training one (different baselines, and a camera orbiting around).

### 3.3. Data Qualities

As visible on the left-hand side of Figure 2, Charge introduces a large diversity of scenes posing challenging and interesting problems for 3D reconstruction methods. Examples include a scene with large open bounds and a smaller dynamic subject (020\_0020), with a large amount of movement (040\_0040), with a large area of dynamic content (070\_0123), or highly non-rigid elements (050\_0130).

With the development of 3DGs, the high-resolution evaluation became viable and is arguably preferable. Thus, we render our dataset in a resolution of **2048** × **858**. Further, we provide a high-speed capture in **96 fps**. Additionally, thanks to the synthetic nature of our data, we are able to provide highly precise camera poses in contrast to real-world captures that have to rely on estimations. Finally, along with *RGB images*, we supply **metric depth**, **optical flow**, **normals**, **UV maps**, **object segmentation**, and **dynamic content masks**.

In total, Charge offers **8** diverse scenes, each rendered with **25+16** dense setup cameras, **9+10** sparse setup cameras, and **4+16** monocular setup cameras. This accounts for

a total of **185 600** frames available, providing a larger scale of data than any other existing datasets (see Tab. 1).

## 4. Benchmark

We evaluate the Charge dataset with a selection of methods representing the state-of-the-art in multi-view and monocular Gaussian Splatting reconstruction. We report a large selection of metrics, introducing a measure of difficulty for each task, and analyse the results focusing on challenges available in our dataset that emphasise problems that are difficult for current methods to deal with.

### 4.1. Metrics

In our evaluation, we report commonly used metrics, such as PSNR, SSIM [30], and LPIPS [35]. Further, for PSNR, we include the metric calculated within the mask of dynamic and static content (PSNR-D and PSNR-S). Similarly, for SSIM and LPIPS we report a version of these metrics calculated for dynamic content based on a tight bounding box of the dynamic mask (SSIM-D, LPIPS-D).

Additionally, we propose to quantify the difficulty of each task. To this end, we suggest calculating a parameter indicating an overlap between the field of views of the testing camera with respect to training cameras. To this end, for each testing view, we reproject the image plane into all training views obtaining coverage masks -  $\{m_i\}$  (effectively saying which area of the testing view is visi-

Table 4. Quantitative evaluation results of Charge dataset - Sparse setup, -D denotes metrics on dynamic-only areas, -S static only and  $FOV_O$  quantifies the field-of-view overlap between testing and training views (*i.e.* harder when lower). Best performer.

Method	Views	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	$FOV_O$
<b>Sparse</b>									
4DGs [31]	3	19.71	20.71	20.28	0.776	0.740	0.358	0.416	0.54
STG [17]		18.80	20.15	19.04	0.753	0.721	0.371	0.418	0.54
Ex4DGs [11]		19.53	20.34	20.05	0.759	0.717	0.350	0.400	0.54
4DGs [31]	6	23.93	24.89	24.29	0.840	0.810	0.277	0.338	0.62
STG [17]		22.39	23.61	22.57	0.820	0.790	0.295	0.361	0.62
Ex4DGs [11]		22.07	23.30	22.31	0.813	0.781	0.299	0.348	0.62
4DGs [31]	9	26.67	26.51	27.45	0.874	0.840	0.226	0.301	0.64
STG [17]		24.52	24.96	25.03	0.850	0.815	0.260	0.347	0.64
Ex4DGs [11]		24.50	26.26	24.73	0.859	0.829	0.225	0.282	0.64



Figure 4. Example results of rendering in Charge dataset evaluation - Dense setup. Best viewed zoomed in.

ble from the given training view). Further, we sum up all such masks and normalise them by the number of pixels in training views  $n_{train} \cdot HW$ , obtaining a weighted covisibility proxy (where pixels seen by more training views have a value closer to 1). Therefore, averaging for  $n_{test}$  test views, the field of view overlap is expressed as:

$$FOV_O = \frac{1}{n_{test}} \left( \frac{\sum_{n_{train}} m_i}{n_{train} \cdot HW} \right) \quad (1)$$

Finally, we average the value for all the test views in the given task to obtain an indication of task difficulty. Note, that for the reprojection, one needs to use depth. In our experiments, we use median depth for the given image. We find that using real depth values for the projected point, using median depth, or using a sensibly chosen handcrafted value does not result in significant value deviations for  $FOV_O$ . A more detailed analysis, along with the breakdown of the metrics, including separation per scene is available in the Supplementary Material.

## 4.2. Results

We provide evaluation for all 3 setups in our dataset, namely Dense, Sparse, and Mono. Therefore, we use 4D Gaussian Splatting [31] to train all sequences in all setups, as it is a method suitable for both multi- and single-view reconstruction. Further, we use Spacetime Gaussians [17] and Ex4DGs [11] to evaluate Dense and Sparse scenarios. Finally, in a monocular setting, we add 3 dedicated methods, Deformable 3D Gaussians [32], SC-GS [9], and MoSca [12]. All methods were trained on full-length sequences and evaluated in full resolution of data in Charge.

## 4.3. Dense

The results of the experiments on the Dense setup of the Charge dataset are presented in Table 3 (top rows). Additionally, selected qualitative samples can be seen in Figure 4. We can observe PSNR results of 28.94, 29.29, and 29.75. This indicates that Charge poses a good challenge for current state-of-the-art methods. In Fig. 4 (left side) we can see that all methods struggle with reconstructing a splash of paint which leads us to believe that even in the dense multi-view camera setup, the reconstruction of the dynamics of a highly non-rigid object is yet to be explored in depth. Further, on the example of the last frame of scene 040\_0040 (Fig. 4 right), we note that our dataset provides a good way of evaluating the effect of the length of the sequence on the reconstruction (with sequences ranging from 93 to 653 frames). The given example shows that 4DGs struggles with reconstructing a long-range sequence with a large amount of movement (note the character coming into a frame). Notably, however, we do not notice a decrease in the performance with the consecutive frames but rather a consistently lower quality of the reconstruction. Finally, unsurprisingly, we can observe the gap between the reconstruction of dynamic and static regions which is reflected in the presented results. This leads us to believe that data like Charge with a large amount of dynamic content is crucial for an insightful evaluation.



Figure 5. Example results of rendering in Charge dataset evaluation - Sparse setup. Top rows - scene 050\_0160, bottom - 060\_0100. Best viewed zoomed in.



Figure 6. Example results of rendering in Charge dataset evaluation - Mono setup, selected trajectory types. Test cameras left to right: static camera, rig camera - small baseline, rig camera - orbiting around train, static camera. Best viewed zoomed in.

#### 4.4. Sparse

In Table 4 we present the results of the evaluation on the Sparse setup of the Charge dataset. Note that as indicated in Figure 2 (right), the sparse camera setup does not overlap with the dense one. Therefore, the corresponding numerical values should not be directly compared. However, based on the values of the field of view overlap, we notice that sparse rendering is significantly harder than dense reconstruction. Additionally, we note that the difficulty increase from 6 to 3 training views is higher than from 9 to 6 training views. An example selection of scenes trained and rendered in all scenarios (with 3, 6, and 9 input views) is shown in Figure 5. We can observe that in the lower camera regime, 4DGS and Ex4DGS perform slightly better than STG, indicating that

the selection of the best method for the task is configuration-dependent. Further, we can clearly observe, both visually, and in the presented metrics, a drastic difference in performance with respect to the number of training cameras. In Figure 5 we can see that even in 9-views case, the renderings exhibit a lack of fine details (*e.g.* hands in the example). Further, with 6 training views, we notice an increasing number of background missing or incorrect gaussian. Finally, 3 views present a very hard case for the benchmarked methods leading to very artifact-filled renders. Interestingly, the differences in the reconstruction of dynamic and static content are not as prominent in the Sparse setup as they were in the Dense one (to the extent of dynamic content being reconstructed better than static in the 6-view case). We be-

lieve that the decrease in the overlap between cameras leads to higher uncertainties, especially in disoccluded areas, as well as edge areas, seen by a very low number of cameras.

#### 4.5. Mono

We propose 4 configurations for evaluating monocular trajectories and provide evaluation separated as such, namely *Spline Fast*, *Spline Slow*, *Random Walk Fast*, *Random Walk Slow*. The results from all configurations are presented in Table 3 (bottom rows). A selection of qualitative results for the Mono setup is shown in Fig. 6. This setup is evaluated based on 8 cameras - 4 cameras correspond to central testing cameras from the Dense setup, and 4 further cameras are moving together with the training one (3 represent different baselines in the task of creating stereo pairs, and 1 camera is orbiting around the training one).

Unsurprisingly, we can notice a decrease in field of view overlap (increase in difficulty) for this task when compared to the dense setup. We see slight differences between the configurations of the Mono setup, indicating structured (spline covering the area better) and faster (more area covered) motion to be easier to reconstruct.

We notice a similar performance of 4DGS and D-3DGS, and lower for SC-GS. This may be caused by the fact that SC-GS to provide controllability to the scenes, describes the motion with a relatively low number of parameters. Surprisingly, MoSca (best performer on DyCheck[7]), performs the best only in structural metric, being lower on PSNR. This may be caused by evaluation on our dataset with a large amount of motion. MoSca heavily relies on trajectory estimation in a preprocessing step which seems to be harder on Charge due to larger range of motion and objects moving into the camera view. Additionally, MoSca optimises camera poses during training, and relies on test time optimisation to update test poses introducing uncertainty with respect to underlying reconstruction. This emphasises the need for Charge benchmark allowing evaluation with perfect ground-truth cameras. In Fig. 4 we notice that when reconstructing a scene with a large amount of dynamic content close to the camera (*e.g.* 070\_0123) the methods tend to struggle with the reconstruction of such regions. Similarly, as seen for 010\_0050, we notice how monocular reconstruction is affected by a lack of coverage outside the field of view causing dark areas near the edges.

In Table 5 we provide additional results for the Mono setup separated into static cameras, and cameras moving together with the training camera (Rig cameras). We note that one-stage methods (4DGS, D-3DGS, SC-GS) perform better on rig cameras, whereas MoSca on static ones. This shows that without heavy geometrical constrains (such as MoSca), methods overfit to training trajectory shown by higher performance in the local neighbourhood of the training view. We believe including both types of target cam-

Table 5. Quantitative evaluation results of static and rig cameras in the Mono setup.

	4DGS		D-3DGS		SC-GS		MoSca	
	PSNR	PSNR-D	PSNR	PSNR-D	PSNR	PSNR-D	PSNR	PSNR-D
<b>Rig cameras</b>								
<b>SF</b>	26.48	24.24	26.60	24.38	26.07	25.25	21.31	21.36
<b>SS</b>	25.84	23.53	25.81	24.16	25.16	24.10	23.10	22.00
<b>WF</b>	26.63	24.58	26.09	24.26	24.99	24.80	22.60	21.85
<b>WS</b>	24.80	22.96	24.19	22.80	23.28	22.95	24.51	23.55
<b>Static cameras</b>								
<b>SF</b>	23.23	21.14	23.15	21.45	21.88	21.88	25.48	24.32
<b>SS</b>	22.53	20.38	22.55	20.90	21.42	20.99	23.81	23.66
<b>WF</b>	22.93	21.00	22.59	20.85	20.80	21.29	25.04	23.68
<b>WS</b>	21.95	20.40	21.52	20.42	20.44	20.51	24.07	23.68

eras provides a fuller overview of the performance of the method. Qualitative results in Fig. 6 coincide with intuition regarding static and rig cameras. Namely, stereo reconstruction (060\_0130) is the most straightforward task, static cameras pose a bigger challenge (070\_0123, 020\_0020) similar to a camera orbiting around the training one (010\_0050) notably due to change in relative angle to the training view.

## 5. Conclusions

In this paper, we introduced Charge, a new dataset and benchmark for dynamic novel view synthesis. Our dataset was synthetically rendered from a professionally created animation movie. This enables us to obtain photorealistic data, with detailed shapes and textures as well as intricate movements and interactions. Charge offers several advantages over real-world datasets: (1) various capture setups for different problems (dense and sparse multi-view, and monocular), (2) with high number of testing cameras, and (3) with accurate camera poses, thus increasing the reliability of the evaluation. (4) Charge contains more motion than any other dataset to date, and (5) this motion is more diverse, *i.e.* ranging from small to large displacements. (6) Charge includes rich annotations including 6 data modalities, encouraging the development of new methods and novel evaluation paradigms.

We also extensively tested the performance of SoTA Gaussian Splatting-based methods on this data. We provided a thorough analysis of the selected methods in all proposed setups (Dense, Sparse,  $\times 4$  Mono). Our evaluation emphasises the shortcomings of current approaches by specifically showing areas that need improvement, based on several aspects and input features, *e.g.* camera speed, trajectory style, static vs dynamic performance. Finally, the performance of the state-of-the-art methods in the Charge benchmark shows that the data we propose is challenging, and that it can be an accelerator in developing and evaluating new dynamic NVS approaches.

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# Charge: A Comprehensive Benchmark and Dataset for Dynamic Novel View Synthesis

## Supplementary Material

### 6. Supplementary Video

We attach a video presenting our dataset as supplementary material. The video presents the main characteristics of our dataset, including:

- large motions *i.e.* movements that are fast and long-range in space,
- rigid and non-rigid animation, *e.g.* articulated humanoid robot in contrast to a changing topology of a paint splash,
- a large dynamic content coverage of scenes (images include high dynamic to static content ratio),
- presence of open bound scene,
- intricate lighting.

Further, we present camera setups, including Dense, Sparse and Mono showing their relative position on the scene. Finally, we show the modalities included in our data, *i.e.* depth, segmentation, dynamic content mask, surface normals, and optical flow.

### 7. Example Images

We attach a set of example images from our dataset. The images belong to one scene and contain:

- a set of images from training cameras in Dense setup (first frame of the animation only),
- a set of images from training cameras in Sparse setup (first frame of the animation only),
- a complete sequence from Mono - Random Walk - Fast setup (converted to a video) including visualisation of depth, segmentation, optical flow, surface normals and dynamic mask.

### 8. Field of View Overlap

In this section, we extend the analysis of the proposed field of view overlap parameter. In the main manuscript, we propose to calculate the projection of a test image plane into training views and calculate  $FOV_O$  based on a weighted average across all corresponding training views. This serves as an estimation of camera coverage between test and training views and can be treated as a proxy for the difficulty of reconstruction.

Notably, the value of such a parameter is dependent on the depth in which we place the projection plane. Here, we consider 3 possible scenarios:

- ground truth depth values for corners of the image plane,
- median value of the true depth in the whole image,
- reasonably chosen custom value (here, we set it to 5m for all scenes).

Table 6. Field of view overlap values calculated per scene for each experiment setup (values for all Mono setups averaged).

	Scene	Real	Median	Custom
Dense	010_0050	0.63	0.67	0.67
	020_0020	0.76	0.80	0.91
	040_0040	0.63	0.85	0.85
	050_0130	0.42	0.43	0.45
	050_0160	0.55	0.59	0.60
	060_0100	0.68	0.73	0.75
	060_0130	0.63	0.68	0.68
	070_0123	0.37	0.84	0.93
Sparse - 3	010_0050	0.50	0.51	0.51
	020_0020	0.62	0.63	0.71
	040_0040	0.55	0.61	0.61
	050_0130	0.34	0.34	0.36
	050_0160	0.53	0.54	0.55
	060_0100	0.61	0.64	0.64
	060_0130	0.51	0.52	0.52
	070_0123	0.32	0.62	0.73
Sparse - 6	010_0050	0.59	0.60	0.60
	020_0020	0.72	0.73	0.81
	040_0040	0.65	0.70	0.70
	050_0130	0.37	0.38	0.40
	050_0160	0.61	0.62	0.63
	060_0100	0.72	0.74	0.74
	060_0130	0.59	0.59	0.60
	070_0123	0.34	0.71	0.84
Sparse - 9	010_0050	0.59	0.60	0.60
	020_0020	0.74	0.76	0.86
	040_0040	0.66	0.73	0.73
	050_0130	0.39	0.40	0.42
	050_0160	0.61	0.64	0.64
	060_0100	0.72	0.76	0.76
	060_0130	0.61	0.62	0.62
	070_0123	0.37	0.74	0.88
Mono	010_0050	0.34	0.36	0.36
	020_0020	0.43	0.45	0.49
	040_0040	0.43	0.48	0.48
	050_0130	0.39	0.39	0.39
	050_0160	0.36	0.38	0.38
	060_0100	0.40	0.42	0.42
	060_0130	0.39	0.41	0.41
	070_0123	0.36	0.48	0.49

In Table 6, we present the values of the field of view overlap for the presented experiments setups for all the aforementioned ways of calculation. We can observe that in a

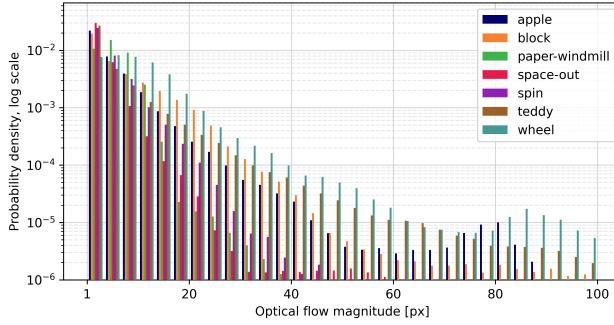


Figure 7. Optical flow histogram for DyCheck dataset.

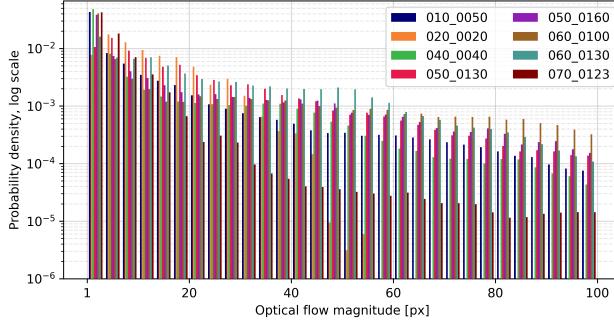


Figure 8. Optical flow histogram for Charge dataset.

majority of cases, all values for the given scene are similar for all 3 methods. Additionally, in most cases, the relative ranking is preserved. We note that the main discrepancy can be seen for scene 070\_0123 in Dense and Sparse setups. This is caused by the fact that this scene is mainly covered by a closeup of an action scene occupying the centre of the field of view. Arguably, in such a case the median value of depth should be more representative with respect to the visibility of pixels between the views.

In summary, we argue that the proposed field of view overlap ( $FOV_O$ ) metric is a good indicator of spatial covisibility between test and training views. Additionally, it is not highly sensitive to the used estimation of depth making it available for use with no ground truth depth available.

## 9. Optical flow details

In Figure 3 we presented a histogram comparing the density of the magnitude of the optical flow for DyCheck and Charge datasets. DyCheck is recognised as the main benchmarking dataset in monocular video reconstruction. We note that Charge presents a significantly larger variety of movement, *i.e.* covering a large distance in the captured frames. Additionally, in Figure 7 and Figure 8 we present detailed histograms of the magnitude of the optical flow for separate scenes of DyCheck and Charge respectively. We see very little high-magnitude movement in DyCheck,

Table 7. FID of selected datasets with DyCheck as a reference.

Dataset	Charge	Neural 3D Video	Technicolor
FID	15.39	14.14	16.87

whereas motion in Charge ranges from lower scale, *e.g.* human in a distance in 020\_0020, up to very dynamic action as in *e.g.* 060\_0100.

## 10. Real-world datasets similarity

We argue that Charge consists of high-quality animations resembling real-world dynamism and texture intricacy. To showcase similarity to real-world datasets, we propose to use the Fréchet inception distance (FID) as the measurement. The metric is commonly used in image generation tasks, and it is a measure of the diversity of the target dataset with respect to the reference dataset. We set DyCheck as the reference dataset (distribution) and calculate FID for Charge, Neural 3D Video, and Technicolor. We present the results in Table 7. Notably, Charge obtains a lower FID score than Technicolor, and slightly higher FID value than Neural 3D Video. This suggests that Charge distribution is reasonably similar in terms of realism and diversity to that of DyCheck, *i.e.* Charge is as similar (or dissimilar) to a real-world dataset (DyCheck) as the real-world datasets are between each other.

## 11. Detailed Results

In addition, we present detailed results of all experiments. In Table 8 we show per-scene results for Dense setup. Similarly, Figure 9 shows additional qualitative examples. Interestingly, the hardest scene for the benchmarked methods was 040\_0040 which is the longest scene that also contains a large amount of movement, specifically a character moving towards the camera rig. Similarly, 070\_0123 poses a significant challenge, it is a scene with a close-up interaction between a humanoid robot and a human in which the dynamic content covers a large part of the field of view and introduces a lot of occluded parts between training views.

Table 9 and Table 10 show results for Sparse setup - configurations with 3, 6, 9 input views. Figure 10 shows additional qualitative examples for all the configurations. It shows varying performance for all the methods depending on the scene. Notably, STG relies on point cloud initialisation for all frames, in contrast to 4DGS and Ex4DGS, showing more dependence on priors and lower performance in low camera regime setup.

Finally, Tables 11 and 12 present results for Mono setup in Spline Fast and Slow, and Random Walk Fast and Slow configurations respectively. Figure 11 shows additional corresponding qualitative examples. Interestingly, MoSca,

which is the current state of the art on DyCheck dataset (by a significant margin), has a relatively lower performance in our benchmark. We believe this emphasises the shortcomings of the approach, and DyCheck dataset. We believe that lower performance of MoSca on Charge can be attributed to the nature of algorithm being catered towards DyCheck data. Namely, the optimisation is performed in several stages, of which the main are: preprocessing - obtaining priors, geometrical optimisation, photometric optimisation. MoSca applies a lot of geometrical constraints in the optimisation process, such as on velocity and acceleration of gaussians, as well as rigidity between neighbouring gaussians. This creates the more compact 3D scene representation, however, leads to decrease in performance in neighbouring views (to which other methods may be overfitted) - see rig cameras against static cameras in Table 5. Similarly, MoSca applies 2D tracking loss based on previously extracted prior. This ties the performance of the reconstruction algorithm to the quality of tracking prior. Tracking algorithms perform better on DyCheck than Charge due to motion being more regular and less dynamic. Additionally, DyCheck test views are placed far away from training camera trajectory. Such a benchmark benefits greatly from having a compact representation, in contrast to placing more gaussians in front of the camera (essentially overfitting to training trajectory) which increases neighbouring view performance. Therefore, we believe it is crucial to have a balanced evaluation such as Charge. Finally, DyCheck provides inaccurate camera poses (due to noisy measurements and sensor drift), and state of the art algorithms perform test time camera optimisation to mitigate that. Essentially, these methods optimise test camera poses such that novel view metrics are maximised. This process entangles the process of reconstruction and camera optimisation, and does not allow for objective assessment of underlying 4D reconstruction. Given the current performance of dynamic-scene camera pose estimation methodologies, we argue that a synthetic dataset such as Charge is the only reliable tool for a fully transparent evaluation, specially for moving monocular videos of dynamic scenes.

## 12. Rendering setup

Charge was rendered in Blender 4.0.2 with the use of Cycles as the rendering engine. The most important settings include a resolution of  $2048 \times 858$ , 256 samples for path tracing, a camera with a focal length of 25mm or 20mm (depending on the scene), and a sensor size of 25mm (original Charge camera settings).

**Setup:** The scenes were rendered on servers each equipped with 4 Nvidia V100 GPUs and a 16-cores (32 threads) of Intel Xeon 8160 CPU. The equivalent rendering time of the whole dataset with one unit of this setup is equal to roughly 1 year.

**License:** Blender Open Movies is a subscription library offering movie production assets under a Creative Commons Attribution 4.0 license. This allows for modification and redistribution under the attribution condition. Charge creators can be found at <https://studio.blender.org/projects/charge/pages/credits/> and are also linked at the dataset download website.

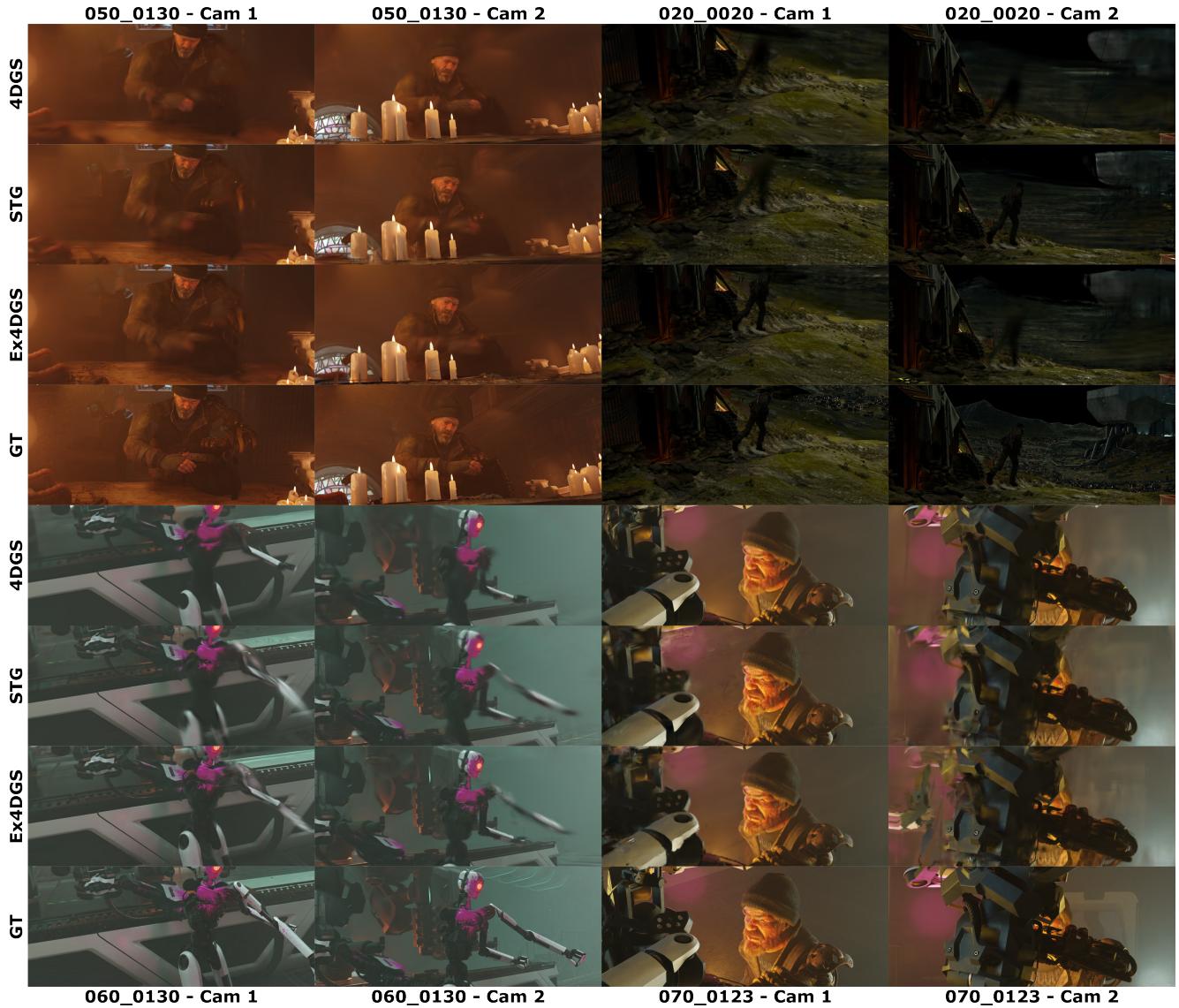


Figure 9. Example results of rendering in Charge dataset evaluation - Dense setup. Best viewed zoomed in.

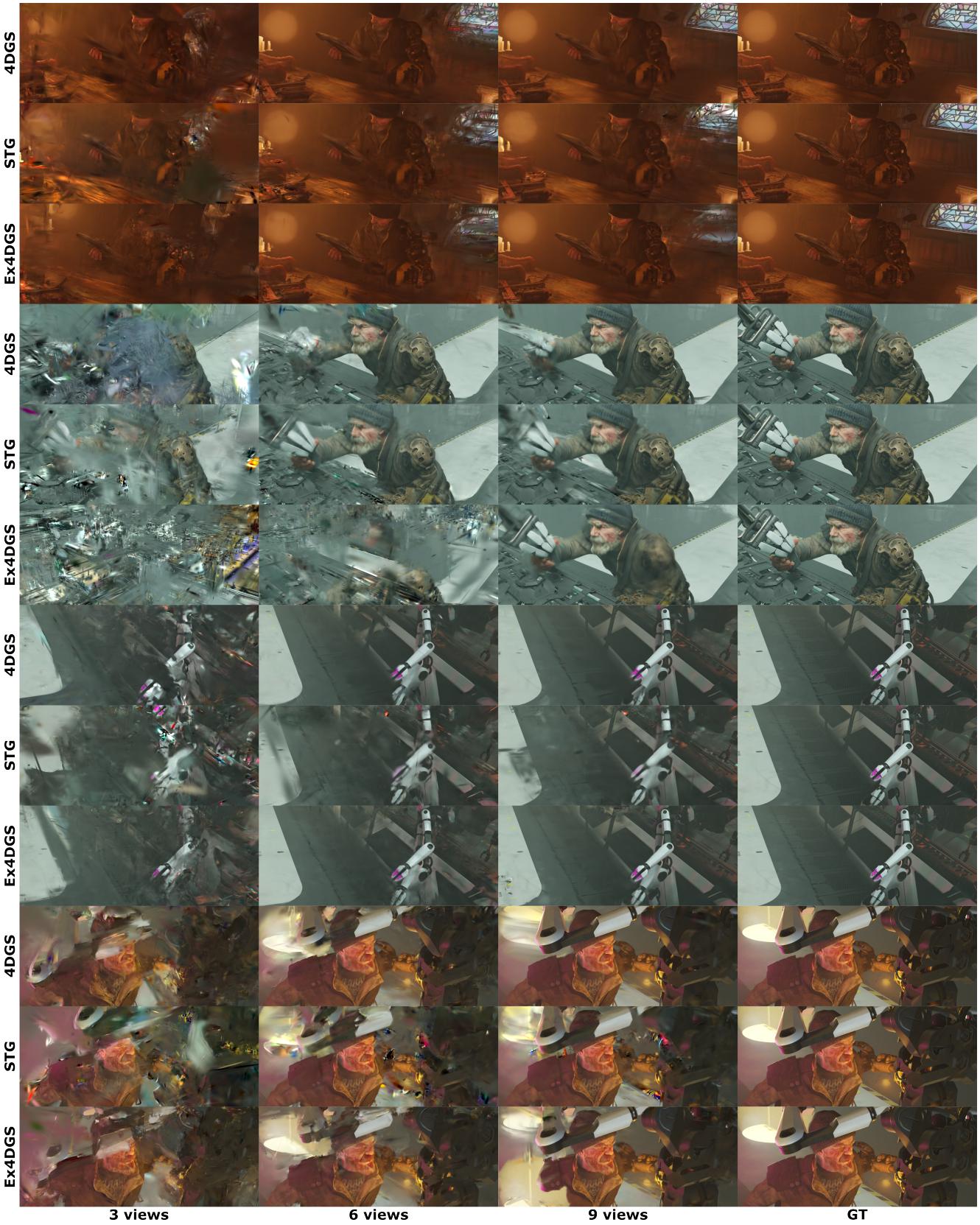


Figure 10. Example results of rendering in Charge dataset evaluation - Sparse setup. Top to bottom scenes: 010\_0050, 040\_0040, 060\_0130, 070\_0123. Best viewed zoomed in



Figure 11. Example results of rendering in Charge dataset evaluation - Mono setup, selected trajectory types. Top half - static cameras, bottom half - rig cameras. Best viewed zoomed in.

Table 8. Quantitative evaluation of Charge dataset - results per scene for Dense setup.

Scene	Method	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	$FOV_O$
<b>Dense</b>									
010_0050	4DGS [31]	31.62	33.32	31.33	0.946	0.938	0.151	0.203	0.669
	STG [17]	32.40	34.34	32.04	0.950	0.945	0.130	0.161	0.669
	Ex4DGS [11]	32.99	34.14	32.79	0.952	0.943	0.121	0.164	0.669
020_0020	4DGS [31]	27.14	28.74	27.13	0.708	0.633	0.412	0.580	0.797
	STG [17]	26.34	31.54	26.31	0.708	0.689	0.282	0.489	0.797
	Ex4DGS [11]	26.99	31.77	26.95	0.767	0.682	0.267	0.503	0.797
040_0040	4DGS [31]	23.16	22.63	24.07	0.775	0.737	0.379	0.436	0.849
	STG [17]	24.45	25.20	24.47	0.813	0.794	0.264	0.284	0.849
	Ex4DGS [11]	24.65	25.16	25.06	0.805	0.774	0.291	0.345	0.849
050_0130	4DGS [31]	31.35	24.04	41.68	0.949	0.884	0.140	0.300	0.433
	STG [17]	32.92	25.96	40.78	0.954	0.901	0.129	0.265	0.433
	Ex4DGS [11]	32.74	26.11	39.49	0.956	0.907	0.114	0.223	0.433
050_0160	4DGS [31]	33.63	32.50	33.96	0.936	0.922	0.154	0.173	0.592
	STG [17]	32.19	31.24	32.41	0.934	0.919	0.138	0.171	0.592
	Ex4DGS [11]	34.92	33.12	35.28	0.947	0.931	0.098	0.138	0.592
060_0100	4DGS [31]	33.43	28.87	34.86	0.944	0.915	0.145	0.250	0.732
	STG [17]	34.17	31.15	34.92	0.948	0.926	0.118	0.192	0.732
	Ex4DGS [11]	34.42	31.93	35.05	0.950	0.930	0.109	0.186	0.732
060_0130	4DGS [31]	25.56	20.50	31.56	0.891	0.865	0.266	0.302	0.680
	STG [17]	27.91	23.13	32.19	0.907	0.888	0.203	0.244	0.680
	Ex4DGS [11]	28.19	24.56	30.90	0.911	0.893	0.185	0.216	0.680
070_0123	4DGS [31]	25.62	24.14	30.18	0.900	0.890	0.202	0.215	0.840
	STG [17]	23.93	22.60	27.54	0.877	0.866	0.281	0.301	0.840
	Ex4DGS [11]	23.07	21.74	27.05	0.858	0.844	0.311	0.334	0.840

Table 9. Quantitative evaluation of Charge dataset - results per scene for Sparse setup - part 1.

Method	Views	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	$FOV_O$
<b>Sparse</b>									
010_0050	4DGS [31]	3	19.29	27.11	0.847	0.869	0.295	0.307	0.514
		6	22.70	31.28	0.891	0.913	0.222	0.237	0.595
		9	28.54	31.81	0.927	0.924	0.201	0.264	0.601
	STG [17]	3	18.93	27.19	0.845	0.863	0.302	0.311	0.514
		6	21.73	31.17	0.866	0.884	0.251	0.270	0.595
		9	23.48	32.04	0.901	0.915	0.225	0.259	0.601
	Ex4DGS [11]	3	18.35	26.02	0.836	0.864	0.310	0.305	0.514
		6	21.07	28.71	0.876	0.895	0.250	0.255	0.595
		9	22.95	32.25	0.905	0.918	0.200	0.216	0.601
020_0020	4DGS [31]	3	23.50	26.52	0.590	0.557	0.421	0.559	0.634
		6	25.45	27.62	0.663	0.596	0.410	0.591	0.734
		9	26.39	28.98	0.699	0.623	0.389	0.583	0.762
	STG [17]	3	20.14	24.72	0.461	0.474	0.393	0.433	0.634
		6	22.84	27.11	0.583	0.561	0.354	0.438	0.734
		9	24.80	28.30	0.658	0.609	0.354	0.525	0.762
	Ex4DGS [11]	3	21.86	23.47	0.541	0.452	0.331	0.432	0.634
		6	23.81	27.19	0.638	0.549	0.293	0.421	0.734
		9	24.65	28.51	0.700	0.595	0.266	0.424	0.762

Table 10. Quantitative evaluation of Charge dataset - results per scene for Sparse setup - part 2.

	Method	Views	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	$FOV_O$
<b>Sparse</b>										
040_0040	4DGS [31]	<b>3</b>	16.95	15.81	17.70	0.680	0.632	0.452	0.494	0.610
		<b>6</b>	21.44	21.79	21.36	0.786	0.757	0.318	0.355	0.704
		<b>9</b>	23.60	24.29	23.59	0.828	0.799	0.253	0.301	0.731
050_0130	STG [17]	<b>3</b>	17.94	18.86	17.63	0.731	0.703	0.402	0.425	0.610
		<b>6</b>	21.08	23.25	20.35	0.800	0.774	0.313	0.350	0.704
		<b>9</b>	22.35	24.47	21.71	0.819	0.794	0.283	0.333	0.731
050_0160	Ex4DGS [11]	<b>3</b>	15.68	15.09	16.06	0.620	0.580	0.535	0.566	0.610
		<b>6</b>	16.50	15.32	17.38	0.696	0.654	0.512	0.565	0.704
		<b>9</b>	23.93	23.62	24.24	0.827	0.799	0.274	0.340	0.731
060_0100	4DGS [31]	<b>3</b>	24.40	18.83	27.93	0.903	0.811	0.192	0.349	0.340
		<b>6</b>	28.99	24.39	31.38	0.938	0.881	0.140	0.248	0.375
		<b>9</b>	30.07	25.36	32.74	0.944	0.888	0.133	0.244	0.398
060_0130	STG [17]	<b>3</b>	24.00	19.08	26.72	0.896	0.809	0.203	0.362	0.340
		<b>6</b>	27.38	22.23	30.21	0.925	0.855	0.175	0.321	0.375
		<b>9</b>	29.49	23.14	34.20	0.936	0.871	0.159	0.300	0.398
070_0123	Ex4DGS [11]	<b>3</b>	22.81	16.86	26.90	0.886	0.785	0.212	0.368	0.340
		<b>6</b>	27.70	23.67	29.64	0.934	0.880	0.138	0.225	0.375
		<b>9</b>	29.06	25.75	30.70	0.944	0.899	0.121	0.192	0.398
070_0160	4DGS [31]	<b>3</b>	18.55	24.89	18.32	0.812	0.806	0.300	0.303	0.543
		<b>6</b>	23.95	29.34	23.75	0.877	0.870	0.190	0.202	0.624
		<b>9</b>	26.56	29.93	26.43	0.913	0.891	0.139	0.186	0.636
070_0190	STG [17]	<b>3</b>	16.82	20.01	16.68	0.793	0.739	0.356	0.408	0.543
		<b>6</b>	22.91	24.40	22.89	0.884	0.832	0.198	0.290	0.624
		<b>9</b>	26.22	25.73	26.36	0.913	0.854	0.159	0.275	0.636
070_0220	Ex4DGS [11]	<b>3</b>	20.07	26.04	19.85	0.824	0.817	0.266	0.270	0.543
		<b>6</b>	22.51	28.88	22.32	0.859	0.868	0.198	0.202	0.624
		<b>9</b>	22.87	30.55	22.62	0.877	0.881	0.170	0.186	0.636
070_0250	4DGS [31]	<b>3</b>	18.56	19.38	18.63	0.812	0.774	0.355	0.394	0.635
		<b>6</b>	26.08	24.52	26.61	0.885	0.844	0.268	0.343	0.737
		<b>9</b>	29.01	26.47	29.92	0.911	0.874	0.199	0.277	0.756
070_0280	STG [17]	<b>3</b>	18.06	18.81	18.03	0.781	0.745	0.403	0.428	0.635
		<b>6</b>	22.80	22.68	22.86	0.849	0.820	0.286	0.351	0.737
		<b>9</b>	25.48	24.52	25.71	0.877	0.846	0.239	0.319	0.756
070_0310	Ex4DGS [11]	<b>3</b>	20.47	20.66	20.59	0.810	0.775	0.323	0.374	0.635
		<b>6</b>	25.00	23.93	25.32	0.872	0.837	0.239	0.314	0.737
		<b>9</b>	27.43	26.25	27.79	0.901	0.871	0.191	0.265	0.756
070_0340	4DGS [31]	<b>3</b>	17.70	14.21	19.10	0.770	0.691	0.442	0.502	0.520
		<b>6</b>	20.76	17.27	22.80	0.822	0.767	0.377	0.425	0.594
		<b>9</b>	23.06	18.05	27.07	0.871	0.823	0.287	0.345	0.622
070_0370	STG [17]	<b>3</b>	16.32	14.25	16.96	0.728	0.661	0.488	0.543	0.520
		<b>6</b>	18.94	16.06	20.00	0.787	0.729	0.417	0.491	0.594
		<b>9</b>	20.55	16.94	22.04	0.820	0.763	0.364	0.461	0.622
070_0400	Ex4DGS [11]	<b>3</b>	17.66	14.83	18.61	0.748	0.670	0.453	0.508	0.520
		<b>6</b>	21.26	19.13	22.09	0.820	0.772	0.351	0.391	0.594
		<b>9</b>	23.24	20.84	24.33	0.850	0.810	0.292	0.339	0.622
070_0430	4DGS [31]	<b>3</b>	18.74	18.90	18.80	0.794	0.783	0.406	0.418	0.621
		<b>6</b>	22.09	22.95	21.25	0.857	0.847	0.295	0.304	0.705
		<b>9</b>	26.12	27.15	25.51	0.901	0.895	0.204	0.208	0.744
070_0460	STG [17]	<b>3</b>	18.22	18.29	18.27	0.786	0.776	0.418	0.429	0.621
		<b>6</b>	21.43	21.97	20.78	0.847	0.839	0.363	0.373	0.705
		<b>9</b>	23.79	24.55	22.99	0.877	0.870	0.293	0.303	0.744
070_0490	Ex4DGS [11]	<b>3</b>	19.34	19.74	19.15	0.805	0.795	0.367	0.378	0.621
		<b>6</b>	18.70	19.54	17.77	0.806	0.796	0.409	0.415	0.705
		<b>9</b>	21.85	22.33	21.58	0.868	0.860	0.284	0.291	0.744

Table 11. Quantitative evaluation of Charge dataset - results per scene for Mono - Spline Fast and Mono - Spline Slow.

Scene	Method	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	<i>FOVO</i>
<b>Mono - Spline Fast</b>									
010_0050	4DGS [31]	28.88	29.76	28.77	0.926	0.916	0.158	0.218	0.318
	D-3DGS [32]	28.36	30.98	28.03	0.932	0.924	0.110	0.141	0.318
	SC-GS [9]	22.64	32.15	21.59	0.902	0.912	0.153	0.156	0.318
	MoSca [12]	25.69	27.93	25.41	0.949	0.939	0.195	0.263	0.318
020_0020	4DGS [31]	26.32	28.15	26.31	0.667	0.606	0.421	0.598	0.413
	D-3DGS [32]	27.84	27.67	27.89	0.816	0.633	0.167	0.400	0.413
	SC-GS [9]	26.41	26.93	26.43	0.727	0.586	0.217	0.468	0.413
	MoSca [12]	23.35	23.99	23.35	0.548	0.523	0.376	0.444	0.413
040_0040	4DGS [31]	18.68	17.58	19.81	0.759	0.723	0.365	0.411	0.467
	D-3DGS [32]	20.25	20.19	20.52	0.792	0.766	0.358	0.383	0.467
	SC-GS [9]	21.18	21.56	21.23	0.800	0.780	0.333	0.347	0.467
	MoSca [12]	18.57	18.61	18.68	0.797	0.772	0.415	0.443	0.467
050_0130	4DGS [31]	26.19	19.58	33.21	0.910	0.799	0.177	0.373	0.402
	D-3DGS [32]	24.94	18.34	31.79	0.909	0.792	0.189	0.426	0.402
	SC-GS [9]	25.48	18.92	31.95	0.906	0.784	0.156	0.336	0.402
	MoSca [12]	27.32	21.74	31.28	0.959	0.858	0.103	0.243	0.402
050_0160	4DGS [31]	25.52	23.39	25.85	0.866	0.820	0.201	0.252	0.335
	D-3DGS [32]	25.58	22.55	26.19	0.882	0.810	0.190	0.282	0.335
	SC-GS [9]	27.21	26.99	27.37	0.893	0.864	0.177	0.205	0.335
	MoSca [12]	24.42	24.59	24.52	0.917	0.872	0.201	0.271	0.335
060_0100	4DGS [31]	29.57	25.46	30.99	0.924	0.880	0.157	0.268	0.426
	D-3DGS [32]	25.88	23.92	26.95	0.893	0.856	0.193	0.260	0.426
	SC-GS [9]	25.70	24.33	26.33	0.891	0.847	0.194	0.262	0.426
	MoSca [12]	26.42	26.67	26.56	0.947	0.914	0.150	0.221	0.426
060_0130	4DGS [31]	21.65	17.21	25.04	0.835	0.801	0.383	0.427	0.354
	D-3DGS [32]	21.78	16.81	26.47	0.865	0.830	0.236	0.290	0.354
	SC-GS [9]	21.42	17.45	24.53	0.820	0.799	0.289	0.325	0.354
	MoSca [12]	22.11	19.80	23.24	0.877	0.846	0.295	0.342	0.354
070_0123	4DGS [31]	22.01	20.42	28.05	0.831	0.808	0.251	0.270	0.476
	D-3DGS [32]	24.40	22.84	30.04	0.863	0.846	0.169	0.173	0.476
	SC-GS [9]	21.75	20.20	27.72	0.832	0.810	0.216	0.229	0.476
	MoSca [12]	19.27	19.39	19.73	0.833	0.811	0.308	0.333	0.476
<b>Mono - Spline Slow</b>									
010_0050	4DGS [31]	23.00	26.09	22.40	0.882	0.884	0.220	0.271	0.351
	D-3DGS [32]	22.87	28.15	22.02	0.888	0.889	0.152	0.176	0.351
	SC-GS [9]	22.03	29.94	21.00	0.895	0.899	0.169	0.169	0.351
	MoSca [12]	24.71	28.16	24.15	0.951	0.944	0.159	0.232	0.351
020_0020	4DGS [31]	25.69	26.10	25.71	0.638	0.574	0.428	0.615	0.428
	D-3DGS [32]	27.20	25.24	27.27	0.807	0.586	0.150	0.383	0.428
	SC-GS [9]	26.10	27.14	26.10	0.757	0.595	0.189	0.430	0.428
	MoSca [12]	23.84	25.21	23.84	0.586	0.553	0.331	0.423	0.428
040_0040	4DGS [31]	18.91	17.74	20.11	0.762	0.722	0.342	0.395	0.468
	D-3DGS [32]	19.76	19.17	20.43	0.783	0.755	0.352	0.386	0.468
	SC-GS [9]	19.89	19.14	20.69	0.785	0.755	0.342	0.375	0.468
	MoSca [12]	18.92	18.37	19.55	0.808	0.773	0.393	0.446	0.468
050_0130	4DGS [31]	26.83	19.95	34.24	0.918	0.808	0.171	0.385	0.357
	D-3DGS [32]	25.25	18.76	31.52	0.908	0.786	0.177	0.397	0.357
	SC-GS [9]	25.04	18.29	31.85	0.908	0.776	0.164	0.375	0.357
	MoSca [12]	26.21	20.15	30.98	0.948	0.826	0.119	0.302	0.357
050_0160	4DGS [31]	28.98	25.49	29.71	0.912	0.856	0.170	0.223	0.353
	D-3DGS [32]	25.88	24.29	26.32	0.865	0.819	0.174	0.230	0.353
	SC-GS [9]	24.64	24.92	24.75	0.865	0.832	0.199	0.226	0.353
	MoSca [12]	22.72	24.54	22.64	0.904	0.861	0.190	0.252	0.353
060_0100	4DGS [31]	28.55	24.92	29.89	0.921	0.878	0.180	0.295	0.398
	D-3DGS [32]	27.23	25.46	27.90	0.898	0.857	0.176	0.234	0.398
	SC-GS [9]	26.04	23.53	26.76	0.886	0.831	0.192	0.262	0.398
	MoSca [12]	27.94	26.68	28.35	0.945	0.908	0.149	0.235	0.398
060_0130	4DGS [31]	21.07	16.46	24.66	0.833	0.791	0.333	0.390	0.377
	D-3DGS [32]	21.90	17.00	26.26	0.866	0.828	0.248	0.304	0.377
	SC-GS [9]	21.02	17.24	23.70	0.821	0.795	0.313	0.342	0.377
	MoSca [12]	24.14	21.30	25.66	0.897	0.865	0.252	0.308	0.377
070_0123	4DGS [31]	20.44	18.88	26.51	0.809	0.783	0.287	0.311	0.475
	D-3DGS [32]	23.39	22.14	27.44	0.852	0.834	0.199	0.208	0.475
	SC-GS [9]	21.55	20.15	26.33	0.824	0.803	0.236	0.251	0.475
	MoSca [12]	19.13	18.24	21.86	0.813	0.790	0.355	0.387	0.475

Table 12. Quantitative evaluation of Charge dataset - results per scene for Mono - Random Walk Fast and Mono - Random Walk Slow.

Scene	Method	PNSR	PNSR-D	PNSR-S	SSIM	SSIM-D	LPIPS	LPIPS-D	<i>FOVO</i>
<b>Mono - Walk Fast</b>									
010_0050	4DGS [31]	26.84	28.39	26.52	0.922	0.914	0.168	0.228	0.370
	D-3DGS [32]	28.74	29.68	28.83	0.935	0.919	0.114	0.151	0.370
	SC-GS [9]	22.44	31.79	21.32	0.899	0.914	0.147	0.145	0.370
	MoSca [12]	26.21	28.77	25.78	0.959	0.950	0.151	0.223	0.370
020_0020	4DGS [31]	26.46	28.04	26.45	0.671	0.612	0.399	0.597	0.482
	D-3DGS [32]	27.35	27.74	27.36	0.807	0.632	0.149	0.383	0.482
	SC-GS [9]	26.00	27.63	25.98	0.742	0.599	0.183	0.389	0.482
	MoSca [12]	23.97	25.03	23.96	0.601	0.548	0.329	0.410	0.482
040_0040	4DGS [31]	20.77	19.64	22.06	0.772	0.734	0.335	0.382	0.486
	D-3DGS [32]	21.29	21.20	21.72	0.801	0.778	0.332	0.363	0.486
	SC-GS [9]	20.84	21.02	21.04	0.798	0.774	0.340	0.366	0.486
	MoSca [12]	18.92	18.55	19.54	0.806	0.774	0.394	0.445	0.486
050_0130	4DGS [31]	26.03	19.57	32.30	0.904	0.791	0.193	0.393	0.393
	D-3DGS [32]	24.48	18.03	30.81	0.896	0.765	0.200	0.430	0.393
	SC-GS [9]	23.98	18.23	28.90	0.852	0.740	0.211	0.420	0.393
	MoSca [12]	26.98	21.20	31.48	0.947	0.849	0.137	0.294	0.393
050_0160	4DGS [31]	27.62	25.05	28.24	0.884	0.837	0.164	0.225	0.388
	D-3DGS [32]	24.28	22.97	24.52	0.879	0.808	0.212	0.276	0.388
	SC-GS [9]	23.57	24.94	23.57	0.845	0.814	0.219	0.231	0.388
	MoSca [12]	25.30	24.90	25.50	0.911	0.870	0.171	0.239	0.388
060_0100	4DGS [31]	29.52	26.34	30.60	0.924	0.891	0.162	0.261	0.427
	D-3DGS [32]	29.01	27.07	29.66	0.916	0.884	0.137	0.186	0.427
	SC-GS [9]	26.66	26.31	26.95	0.897	0.865	0.188	0.239	0.427
	MoSca [12]	28.20	26.50	28.65	0.946	0.908	0.145	0.227	0.427
060_0130	4DGS [31]	20.59	16.47	23.55	0.812	0.774	0.360	0.407	0.449
	D-3DGS [32]	20.72	16.40	24.35	0.830	0.797	0.256	0.319	0.449
	SC-GS [9]	20.19	16.35	22.83	0.792	0.760	0.325	0.370	0.449
	MoSca [12]	23.15	20.70	24.58	0.882	0.852	0.271	0.317	0.449
070_0123	4DGS [31]	20.41	18.82	24.78	0.789	0.770	0.351	0.377	0.472
	D-3DGS [32]	18.83	17.35	22.66	0.751	0.733	0.333	0.361	0.472
	SC-GS [9]	19.48	18.09	23.16	0.753	0.732	0.332	0.353	0.472
	MoSca [12]	17.82	16.50	21.20	0.803	0.783	0.410	0.447	0.472
<b>Mono - Walk Slow</b>									
010_0050	4DGS [31]	25.50	28.16	25.00	0.912	0.906	0.179	0.235	0.405
	D-3DGS [32]	22.92	29.43	21.97	0.882	0.891	0.146	0.163	0.405
	SC-GS [9]	21.80	30.54	20.69	0.890	0.896	0.163	0.163	0.405
	MoSca [12]	25.40	29.65	24.84	0.961	0.949	0.142	0.221	0.405
020_0020	4DGS [31]	25.61	27.51	25.60	0.650	0.600	0.406	0.592	0.478
	D-3DGS [32]	25.78	24.92	25.80	0.766	0.519	0.150	0.375	0.478
	SC-GS [9]	24.83	26.72	24.82	0.663	0.559	0.179	0.351	0.478
	MoSca [12]	25.69	27.07	25.68	0.676	0.604	0.288	0.406	0.478
040_0040	4DGS [31]	18.96	17.63	20.35	0.754	0.703	0.341	0.407	0.480
	D-3DGS [32]	19.71	18.98	20.40	0.785	0.747	0.350	0.393	0.480
	SC-GS [9]	18.98	19.50	18.97	0.788	0.759	0.348	0.375	0.480
	MoSca [12]	19.66	19.19	20.23	0.817	0.783	0.363	0.412	0.480
050_0130	4DGS [31]	25.51	19.02	32.12	0.905	0.787	0.181	0.394	0.407
	D-3DGS [32]	23.92	17.43	30.22	0.896	0.763	0.198	0.439	0.407
	SC-GS [9]	23.66	17.26	29.68	0.885	0.744	0.204	0.445	0.407
	MoSca [12]	26.73	21.12	30.89	0.953	0.846	0.120	0.285	0.407
050_0160	4DGS [31]	25.52	23.86	25.82	0.860	0.821	0.192	0.247	0.434
	D-3DGS [32]	23.40	21.41	23.87	0.820	0.777	0.211	0.294	0.434
	SC-GS [9]	22.20	23.34	22.17	0.831	0.803	0.238	0.273	0.434
	MoSca [12]	25.04	24.55	25.22	0.902	0.865	0.183	0.249	0.434
060_0100	4DGS [31]	28.49	25.38	29.74	0.912	0.877	0.181	0.274	0.428
	D-3DGS [32]	26.36	25.44	26.90	0.885	0.841	0.188	0.248	0.428
	SC-GS [9]	24.79	22.91	25.47	0.882	0.832	0.202	0.269	0.428
	MoSca [12]	28.28	26.98	28.68	0.938	0.911	0.168	0.227	0.428
060_0130	4DGS [31]	19.25	15.28	22.00	0.790	0.752	0.382	0.428	0.447
	D-3DGS [32]	20.90	16.74	24.22	0.826	0.802	0.291	0.332	0.447
	SC-GS [9]	20.77	17.20	23.13	0.808	0.785	0.309	0.338	0.447
	MoSca [12]	24.66	21.83	26.41	0.913	0.883	0.215	0.266	0.447
070_0123	4DGS [31]	18.18	16.58	24.49	0.757	0.725	0.355	0.387	0.478
	D-3DGS [32]	19.85	18.52	24.69	0.775	0.756	0.279	0.298	0.478
	SC-GS [9]	17.85	16.41	23.16	0.742	0.714	0.308	0.332	0.478
	MoSca [12]	18.86	18.51	19.88	0.810	0.789	0.352	0.379	0.478