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**004** **VOLDOR: Visual Odometry from Log-logistic Dense Optical flow Residuals** 058  
 005 **Appendix** 059  
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 009       Anonymous CVPR submission 060  
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 011       Paper ID 5888 061  
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 014       In the appendix, we first describe our ground plane estimation algorithm coupled with KITTI benchmark in §1. Also, 062  
 015 we provide additional performance comparisons and a detailed performance study in §2. Then we provide implementation 063  
 016 details in §3. Finally, we visualize our results under various scenes using different optical flow inputs in §4. 064  
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**018** **1. Ground Plane Estimation** 065  
 019       In Table 1, we detail our ground plane estimation algorithm coupled with KITTI odometry benchmark. 066  
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 021       **Input:** Estimated depth map  $\theta$  from VOLDOR 067  
 022       **Output:** Ground plane height  $h$  068  
 023           Ground normal vector  $n$  069  
 024       Crop a region of interest (ROI) at the image bottom. 070  
 025       Compute a normal vector  $n_j$  for each pixel  $j$  in the ROI, where  $\|n_j\| = 1$ . 071  
 026       Estimate a height  $h_j$  for each pixel, where  $h_j = n_j \cdot \theta^j K^{-1} [x_j \ y_j \ 1]^T$ . 072  
 027       Compute median height  $h_{med}$ . 073  
 028       Meanshift on the 4-vector space of  $[n_j, h_j/h_{med}]$  with initial start mean  $[0, -1, 0, 1]$ . 074  
 029       If result mean  $[\hat{n}, \hat{h}/h_{med}]$  has near perpendicular normal vector that  $\hat{n} \cdot [0, -1, 0] < \epsilon$  075  
 030           Return the result height  $\hat{h}$  076  
 031       Else 077  
 032           Ground plane registration failed 078

033 **Table 1: Ground plane estimation algorithm.** We estimate a normal vector and height for each pixel in the ROI and scale 087  
 034 the height with its median. Meanshift is applied to find the mode with prior knowledge of the ground normal and the height 088  
 035 scale (median). Finally, we actively check the estimated normal vector to determine if the ground estimate is correct. 089  
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## 038 **2. Additional Experiments**

### 039 **2.1. Comparison with deep-learning VO**

041 As Table 2 shows, we compare our visual odometry result with recent SOTA deep-learning VO methods, where ORB- 095  
 042 SLAM is used as baseline. 096

Method	Seq.09		Seq.10	
	Trans. (%)	Rot. (deg/m)	Trans. (%)	Rot. (deg/m)
ORB-SLAM [3]	15.30	<b>0.003</b>	3.68	0.005
GeoNet [8]	43.76	0.160	35.60	0.138
Zhou <i>et al.</i> [10]	17.84	0.068	37.91	0.178
Zhan <i>et al.</i> [9]	11.92	0.036	12.63	0.034
DeepVO [7]	-	-	8.11	0.088
Wang <i>et al.</i> [6]	9.30	0.034	7.21	0.039
VOLDOR (Ours)	<b>1.61</b>	0.004	<b>1.44</b>	<b>0.004</b>

052 **Table 2: Comparison with recent deep-learning methods on KITTI visual odometry benchmark sequence 09, 10.** 106  
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## 2.2. Detail Performance Study

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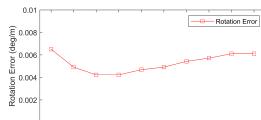
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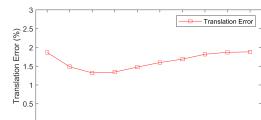
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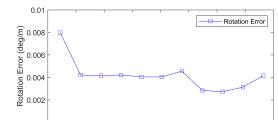
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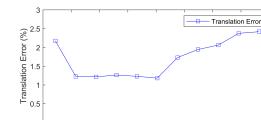
(a) Rotation error over frame



(b) Translation error over frame



(c) Rotation error over speed



(d) Translation error over speed

Figure 1: Performance analysis over frame and speed on KITTI benchmark.

Further, we detail the performance of our method. Due to the camera motion, our geometry representation of first frame's depth map causes the coverage of registerable depth pixels to vary with the frames within the optimization window. Some of the depth pixels can only be registered in a small number of frames, this will yield less reliable depth estimates since they are triangulated from less observations. However, those depth pixels will increase the depth coverage of the frames where they are observed. With different balance between the reliability and coverage of depth pixels, the performance of each frame within the optimization window varies. In Figure 1, we test the performance over 10 frames separately using KITTI dataset. As the result shows, the third and fourth frames usually have the best performance. We will utilize this property when fusing segment estimates as will be described in §3.

Figure 1 (c) (d) shows the performance over different camera moving speed in the KITTI dataset. Our method can stably work with a wide range of speed at 10-50 km/h. When the speed is low, camera baselines are small and the triangulation has large uncertainty, which decreases the performance. When the speed is high, frames have limited overlap and provide little mutual information that also causes a decrease of performance.

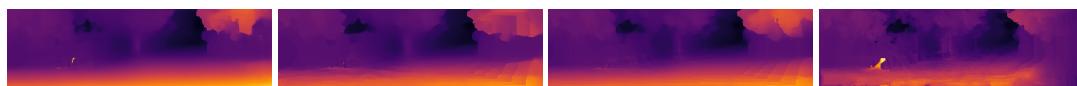
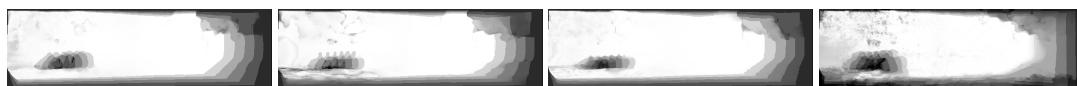
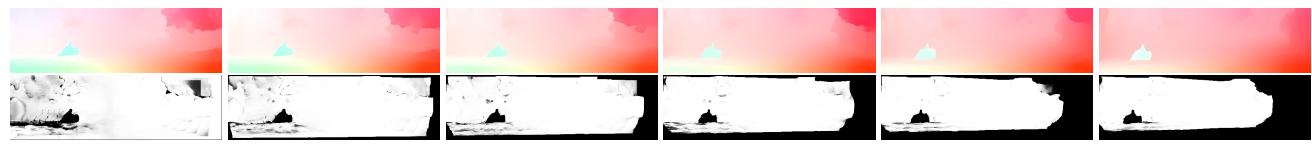
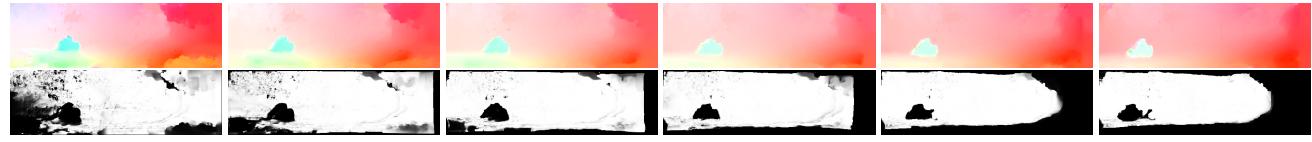
## 3. Implementation Details

**Depth update.** In the depth update process, we sample a depth value from an uniform distribution with inverse depth representation for each pixel, while the best depth value is kept. This process can be done multiple times to achieve better convergence. In practice, we sample one depth value for each pixel when testing for camera pose accuracy, while two times when testing depth accuracy. Finally, we do the propagation scheme from four directions only one time to spread the depth values. While computing the likelihood of a depth value, if a pixel falls out the boundary, we simply set its rigidness from that time step to zero. We use bilinear interpolation to obtain a flow vector on continuous position of observed optical flow field.

**Pose update.** In the pose sampling process, besides only referring to the rigidness map, we also select pixels fall in a certain range of depth. We pick pixels with  $500 > \frac{\theta^j}{t} > 0.1$ , where  $\theta^j$  is the pixel depth value, and  $t$  is the translation vector magnitude. In meanshift process, since we observed a low variance of pose weights, we binarize the weight with a threshold at 0.5 for a faster meanshift implementation. For meanshift initialization, we use the estimated camera pose in the previous iteration. In the case of first iteration, we start with the camera pose of previous time step if the initialization can obtain a kernel weight larger than 0.1. Otherwise, we randomly pick 10 start point and start with the start point with largest kernel weight.

**Truncation.** In the whole workflow, for robustness, we actively detect badly registered frame and truncate the optimization window size. This mainly happens when the camera motion is large, such that the depth map of first frame cannot be registered to the tail frames. We use two criteria to determine a truncation at time step  $t$ , 1) when rigidness map at time  $t$  has less than 2000 inlier pixels, 2) after meanshift for camera pose at time  $t$  converges, the kernel weight is less than 0.01. The truncation truncates the optimize window size to  $t - 1$ . and force the algorithm to run 3 more iterations after truncation to ensure convergence.

**Fusion.** Our method treats each optimization window independently. Thus, we apply a fusion as post-processing to obtain the full visual odometry result. In KITTI experiment, we run the sliding window of window size 6 with step 1, resulted in obtaining 6 pose candidates for each time step. As shown in Fig. 1, the pose quality of each frame in the optimization window varies. In light of this, we pick poses of better quality with higher priority according to the plot.

216 **4. Results** 270  
217218 In this section, we visualize our results under various scenes using four different optical flows[5, 4, 1, 2]. 271  
219220 **4.1. Result - KITTI - Dynamic Foreground** 273  
221222 When there are moving objects at foreground, rigidness maps can correctly segment the object and exclude them from 223 the estimation of depth map. However, the result depth map can still provide correct background depth estimation at regions 224 occluded by dynamic foreground objects using the information from frames where the region is not occluded. 275  
225226 Figure 2: Input image sequence. 281  
227228 Figure 3: Inferred depth map of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow. 285  
229230 Figure 4: Rigidness map sum of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow. 290  
231232 Figure 5: Optical flow fields from PWC-Net and inferred rigidness maps. 297  
233234 Figure 6: Optical flow fields from FlowNet2 and inferred rigidness maps. 305  
235236 Figure 7: Optical flow fields from EpicFlow and inferred rigidness maps. 311  
237238 Figure 8: Optical flow fields from C2F-Flow and inferred rigidness maps. 317  
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## 4.2. Result - KITTI - Forward Motion

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With forward motion, depth pixels become invisible by exiting the field of view at the image boundary, which is reflected in the rigidness maps. Also, occlusions as well as outlier pixels (along object boundaries and the sky region of C2F-Flow and EpicFlow) are clearly indicated by rigidness maps.

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Figure 9: Input image sequence.

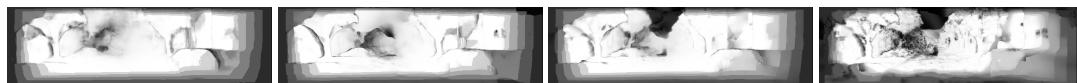
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Figure 10: Inferred depth map of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

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Figure 11: Rigidness map sum of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

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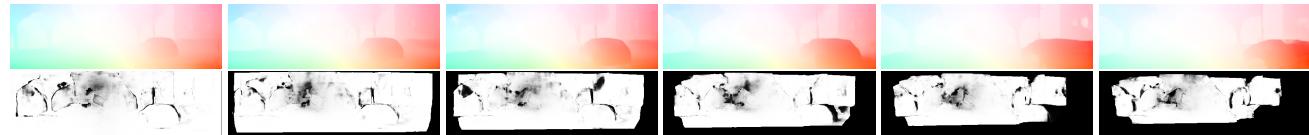


Figure 12: Optical flow fields from PWC-Net and inferred rigidness maps.

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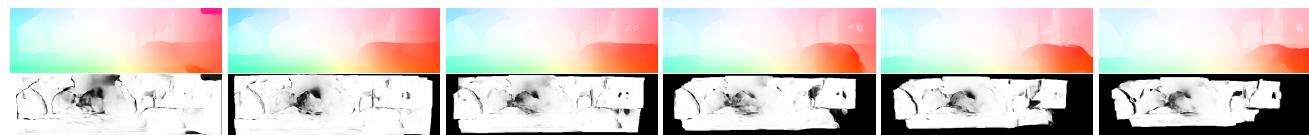


Figure 13: Optical flow fields from FlowNet2 and inferred rigidness maps.

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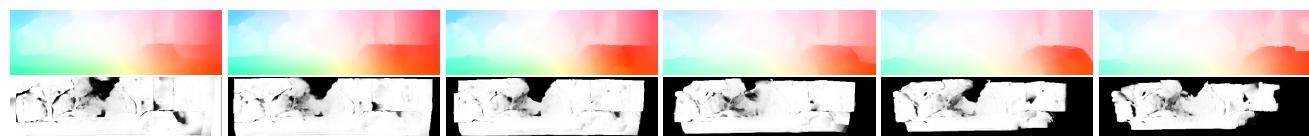


Figure 14: Optical flow fields from EpicFlow and inferred rigidness maps.

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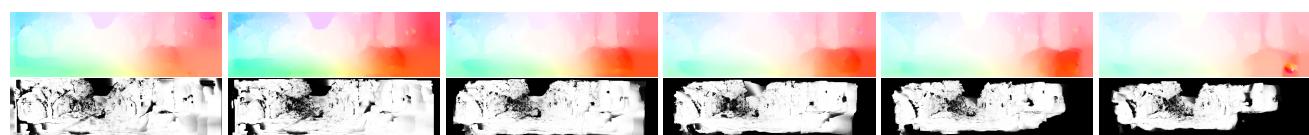


Figure 15: Optical flow fields from C2F-Flow and inferred rigidness maps.

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### 4.3. Result - KITTI - Rotating Motion

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With rotating motion, depth pixels becomes invisible from the side opposite the rotation, which also is reflected in the rigidness maps. Good optical flow methods can usually provide more consistent output depth map along the object and frame boundaries.

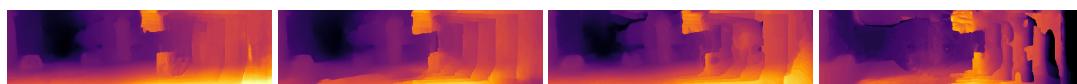
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Figure 17: Inferred depth map of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.



Figure 18: Rigidness map sum of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.



Figure 19: Optical flow fields from PWC-Net and inferred rigidness maps.



Figure 20: Optical flow fields from FlowNet2 and inferred rigidness maps.



Figure 21: Optical flow fields from EpicFlow and inferred rigidness maps.



Figure 22: Optical flow fields from C2F-Flow and inferred rigidness maps.

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#### 4.4. Result - TUM RGB-D - Indoor 1

Indoor capture scenario exhibiting smaller camera motions and diverse motion patterns. Our methods also works well and triangulates consistent depth map.



Figure 23: Input image sequence.

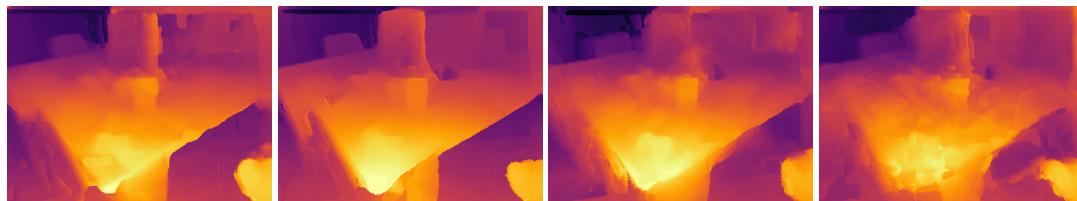


Figure 24: Inferred depth map of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

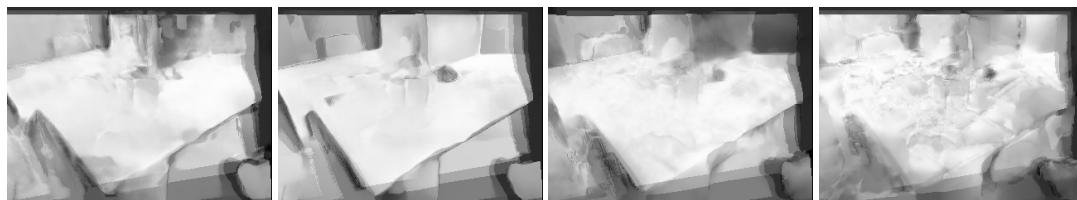


Figure 25: Rigidness map sum of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

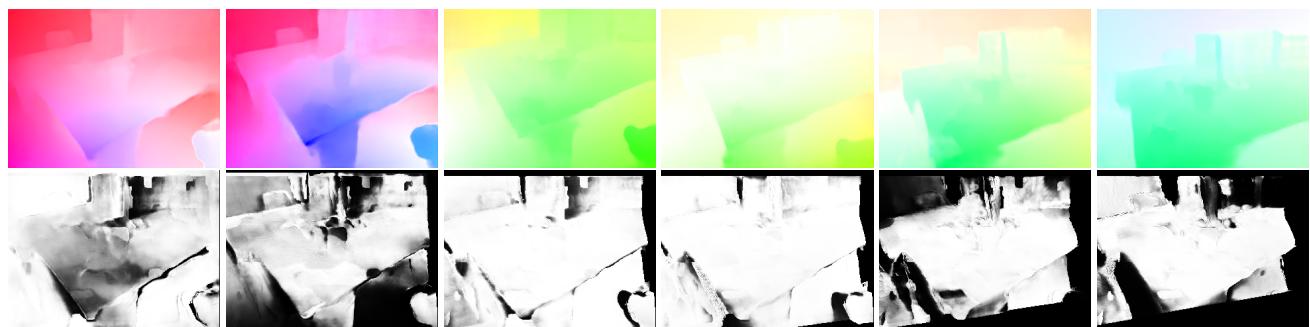


Figure 26: Optical flow fields from PWC-Net and inferred rigidness maps.

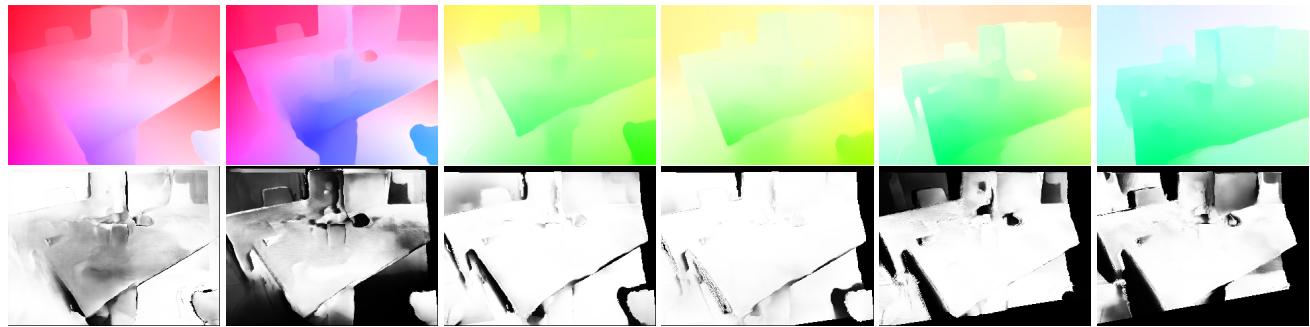


Figure 27: Optical flow fields from FlowNet2 and inferred rigidness maps.

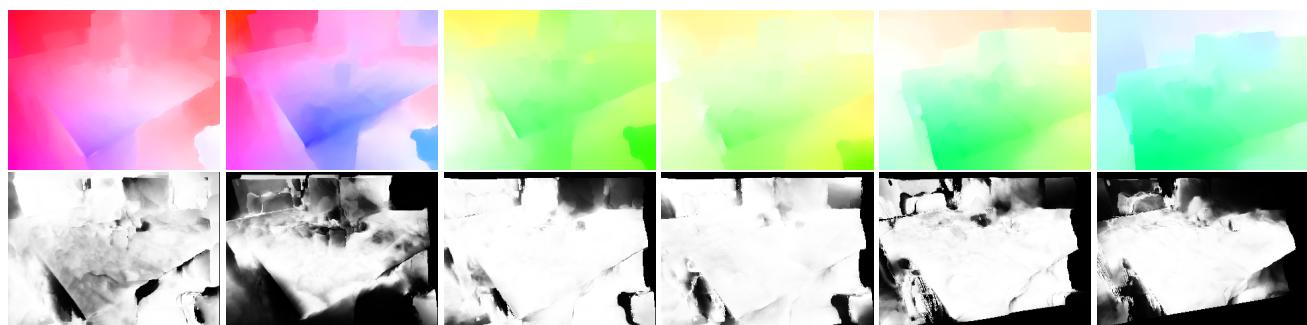
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Figure 28: Optical flow fields from EpicFlow and inferred rigidness maps.

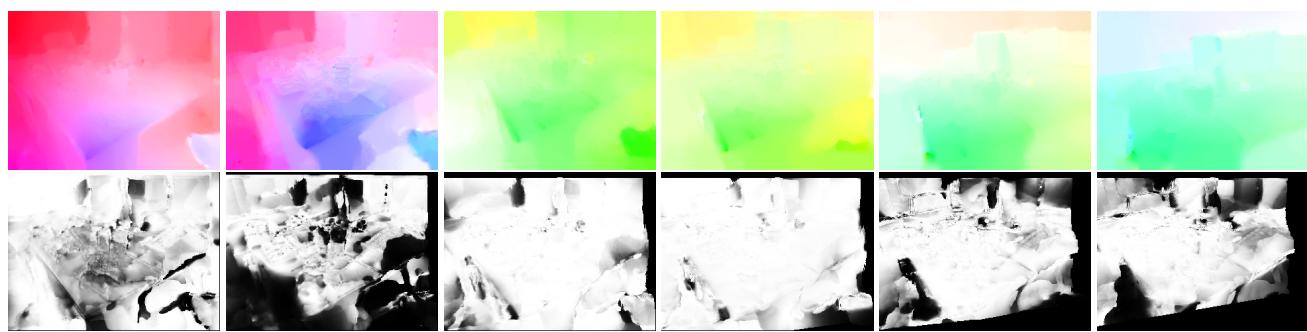
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Figure 29: Optical flow fields from C2F-Flow and inferred rigidness maps.

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#### 4.5. Result - TUM RGB-D - Indoor 2

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Indoor capture scenario exhibiting smaller camera motions and diverse motion patterns. Our methods also works well and triangulates consistent depth map.

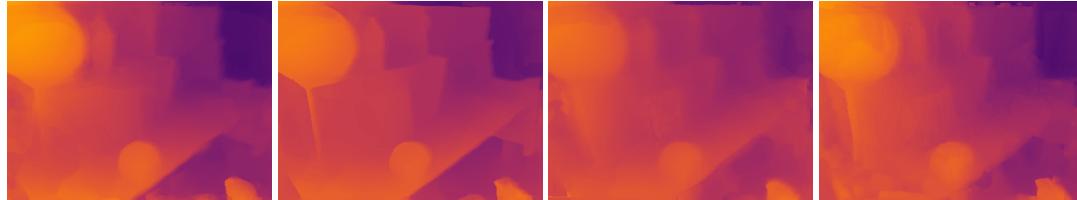
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Figure 30: Input image sequence.

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Figure 31: Inferred depth map of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

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Figure 32: Rigidness map sum of (in order) PWC-Net, FlowNet2, EpicFlow, C2F-Flow.

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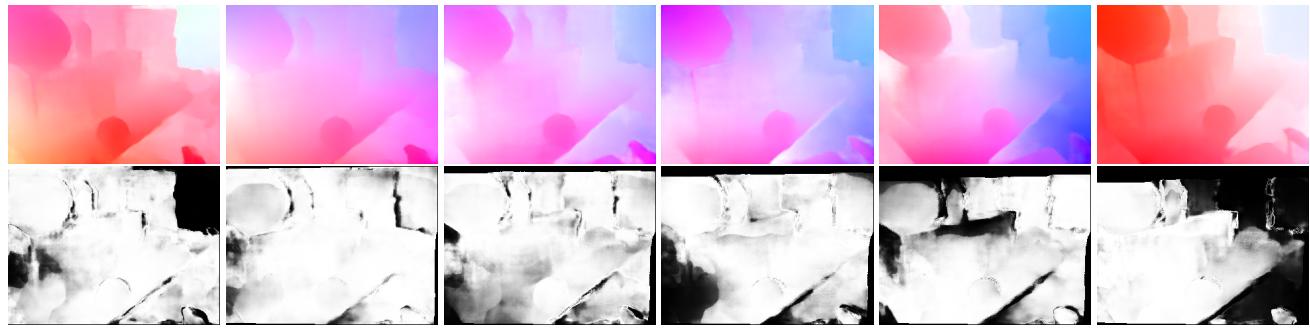


Figure 33: Optical flow fields from PWC-Net and inferred rigidness maps.

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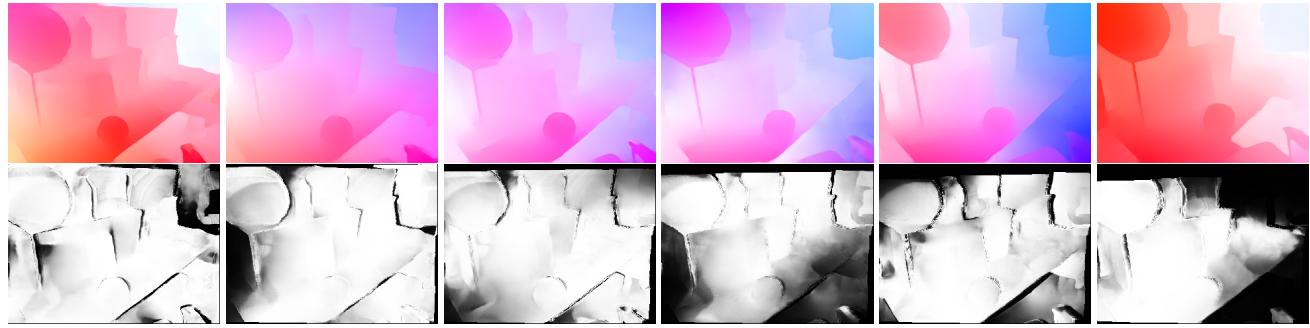


Figure 34: Optical flow fields from FlowNet2 and inferred rigidness maps.



Figure 35: Optical flow fields from EpicFlow and inferred rigidness maps.

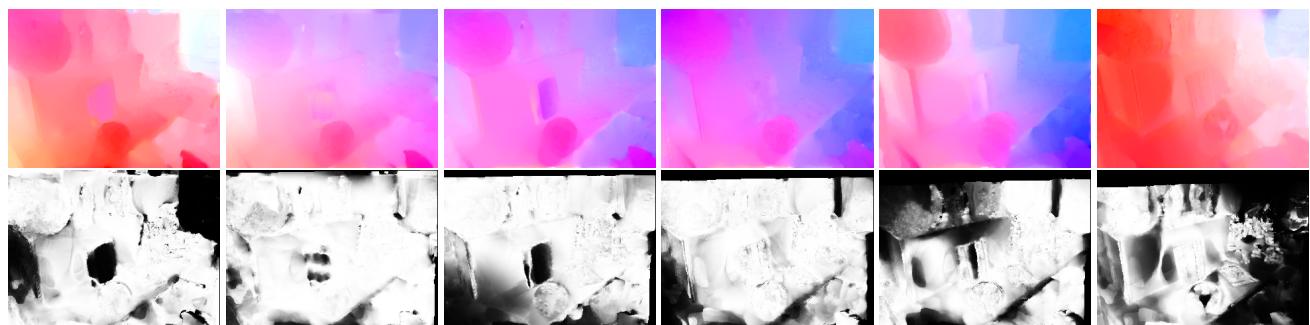


Figure 36: Optical flow fields from C2F-Flow and inferred rigidness maps.

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