

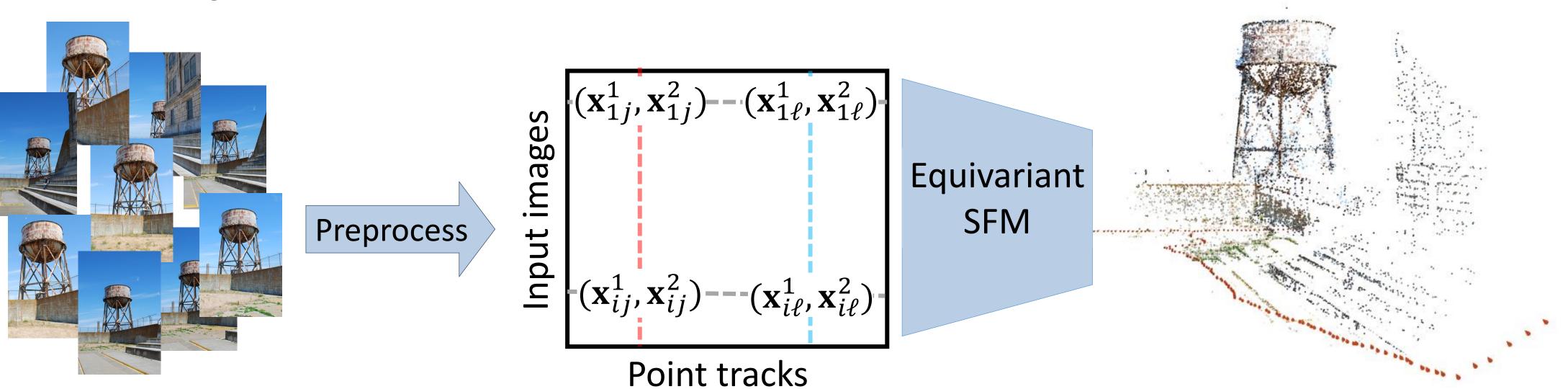
Deep Permutation Equivariant Structure from Motion

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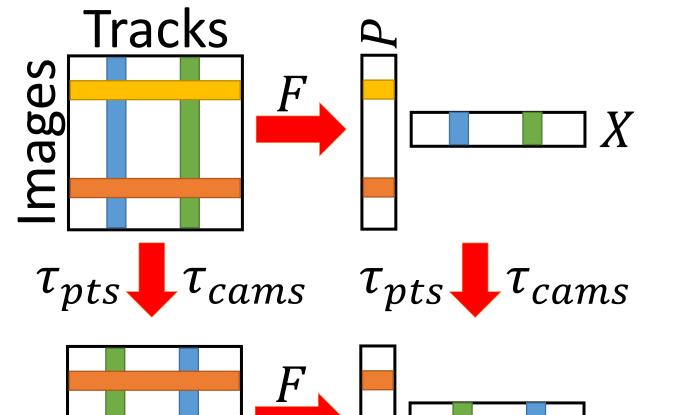
SFM problem definition:

Given images of a static scene, find camera parameters and 3D scene points



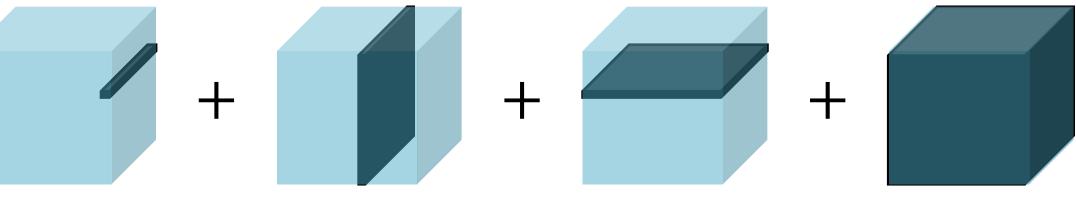
Task symmetries:

Equivariance to permutations of rows and columns

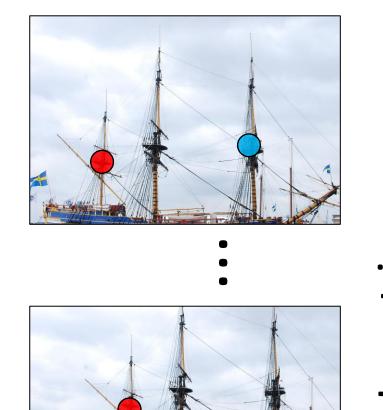


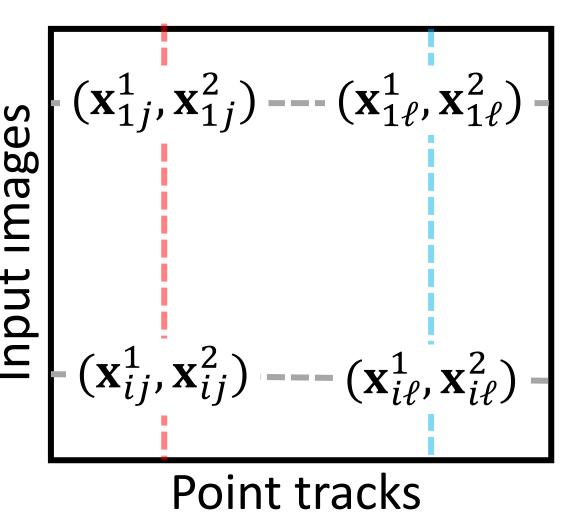
Equivariant layer: equivariant affine function + pointwise activation function (ReLU)

$$\sigma(W_1\widetilde{M}_{ij} + W_2 \sum_{i} \widetilde{M}_{ij} + W_3 \sum_{j} \widetilde{M}_{ij} + W_4 \sum_{i,j} \widetilde{M}_{ij} + b)$$

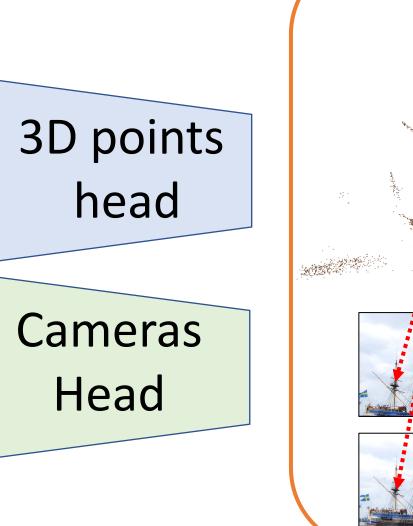


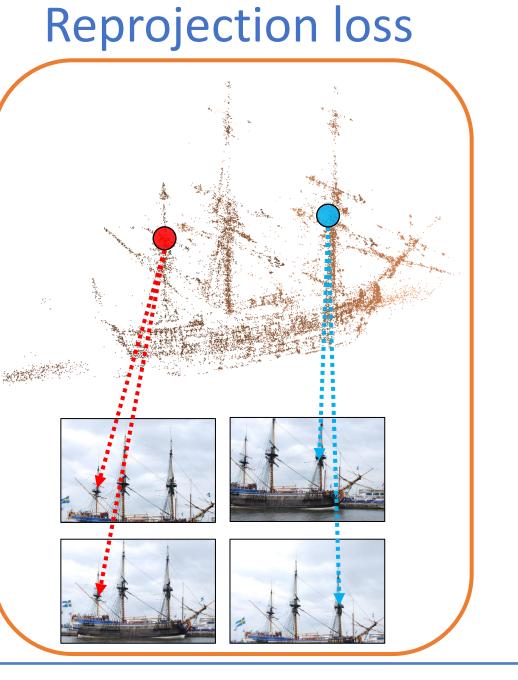
Equivariant-SFM:





Permutationequivariant feature encoder



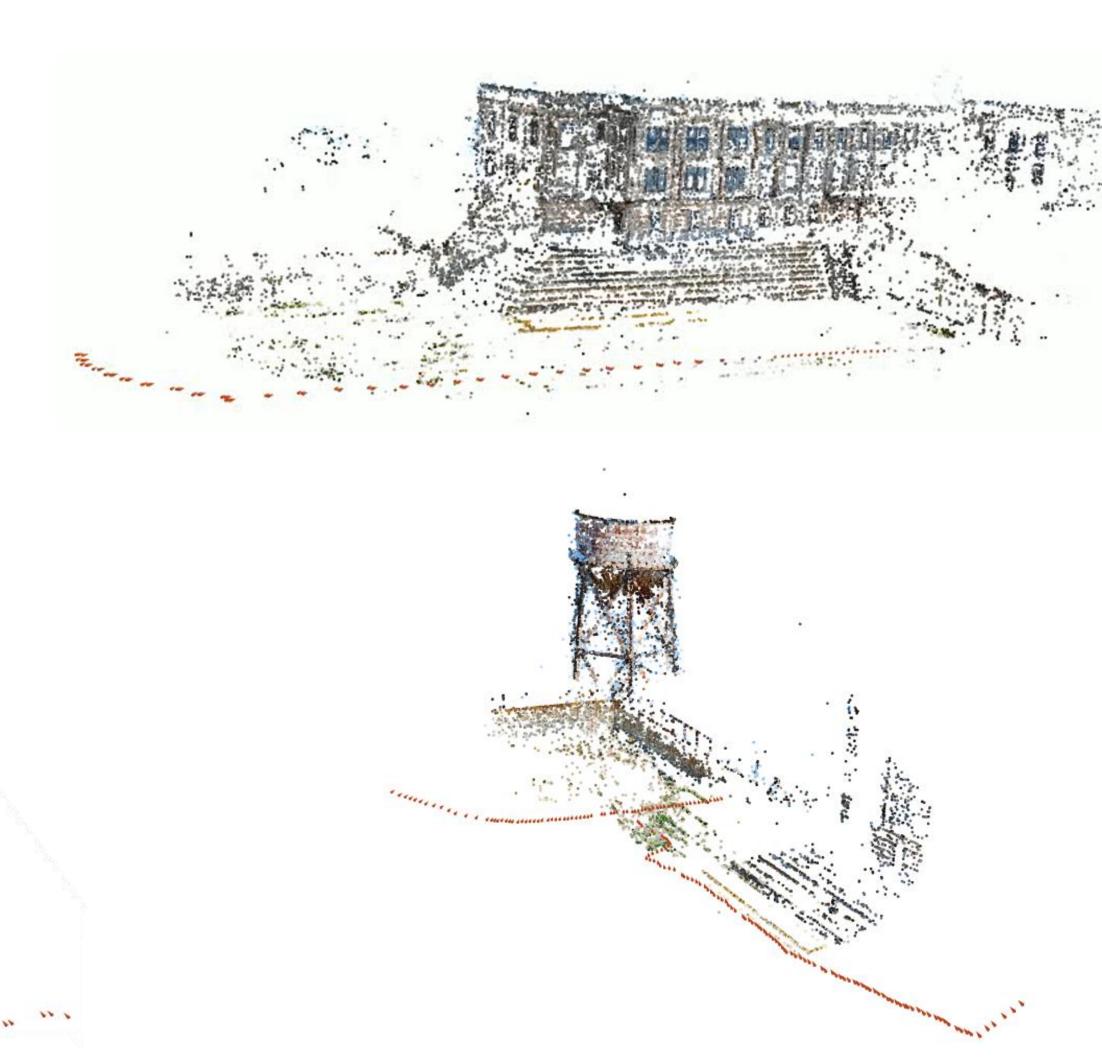


Results:





Learning from multiple scenes



	#Images	#Points	Reprojection Error				
Scan			Single Scene	Inference	Fine Tuning	Opt. (short)	Colmap
Alcatraz Courtyard	133	23674	0.81	0.82	0.81	1.61	0.81
Alcatraz Water Tower	172	14828	0.55	0.55	0.55	4.6	0.55
Drinking Fountain	14	5302	0.31	7.21	0.31	110.85	0.31
Nijo Castle Gate	19	7348	0.73	5.81	0.73	19.0	0.73
Porta San Donato Bologna	141	25490	0.75	1.1	0.79	83.02	0.75
Round Church Cambridge	92	84643	1.54	0.5	1.51	28.17	0.39
Smolny Cathedral	131	51115	0.81	15.15	0.81	2.86	0.81
Cathedral In Barcelona	177	30367	0.89	21.46	0.89	1.06	0.89
Sri Veeramakaliamman	157	130013	0.73	16.92	17.26	90.41	0.71
Yueh Hai Ching Temple	43	13774	0.65	1.16	0.65	37.31	0.65