

# Semantic Localisation via Globally Unique Instance Segmentation

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## 1 Introduction

This document lists and describes four videos submitted as a supplementary material for the main paper.

## 2 Supplementary Video Information

The details of the aforementioned videos are listed below.

- **VID-01-CamVid360-Demo.mp4**

This video shows an illustration of the whole pipeline of semantic localisation via globally unique instance segmentation. It is split into four parts: (i) example of panoramic video, (ii) examples of hand labelled frames, (iii) their propagation and (iv) localisation. Best viewed in panoramic video player.

- **VID-02-CamVid360-Building-and-Tree-Instances-Alig.mp4**

This video illustrates results of globally unique instance segmentation and localisation for CamVid-360 dataset. It uses building and tree instances and label image alignment similarity function to establish image matches. The top left image corresponds to the query image. The top right image corresponds to predicted labels. The bottom left image corresponds to the best matching database image and the bottom right image corresponds to the label image of the best matching database image.

- **VID-03-SceneCity-Small-Missing-Buildings-Building-Alig.mp4**

This video illustrates results of globally unique instance segmentation and localisation for SceneCity dataset. It uses building instances and label image alignment similarity function to establish image matches. Its layout follows the same pattern as in previous video (VID-02).

- **VID-04-Stanford2D3DS-All-Static-Hist.mp4**

This video illustrates results of globally unique instance segmentation and localisation for Stanford-2D-3D-S dataset. It uses all static object instances and label histogram similarity function to establish image matches. Its layout follows the same pattern as in previous video (VID-02).