Supplementary Material:
A Light Touch Approach to Teaching Transformers Multi-view Geometry

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1. Do cross-attention maps from Max-Epipolar Loss correspond to true matching points?

We overlay the cross-attention maps, extracted from the Transformer [4] model trained with Max-Epipolar Loss (\(L_{\text{MaxEPI}}\)), on the original images to see if the location of highest attention coincides with the position of the actual matching point. Fig. 1 shows one such visual illustration. We can see that the peaks of the attention maps loosely coincide with the actual matching points on the corresponding ground-truth epipolar lines.

2. Cross-attention Visualization for mismatched image pair

Similar to Fig. 4 in the main paper, we visualize the cross-attention maps for a pair of mismatched images, as shown in Fig. 2. These cross-attention maps are extracted from a RRT [4] model trained with Epipolar Loss (\(L_{\text{EPI}}\)).

3. Qualitative examples

In Figures 4-14, we provide a few qualitative results on the CO3D-Retrieve benchmark (Figures 4-8) and the Stanford Online Products [2] dataset (Figures 9-14). We visually compare the top-5 retrievals obtained with the Global Retrievial (R50) model, Reranking Transformer [4] model and a reranking model trained with our Epipolar Loss. We also accompany each example with its corresponding Precision-Recall curve, which provides a more detailed perspective on the retrieval performance.

In the CO3D-Retrieve benchmark, the maximum number of reference images per query is 4. So, for all the examples shown, the Precision-Recall curve for our method saturates at Precision = 1.0 since the top-4 retrievals are correct.

4. Visualization of Attention Maps

For the sake of clarity, we describe, with an example, how the cross-attention map predicted by our Transformer model (trained with Epipolar Loss) contains information about the true epipolar geometry between the input image pair. Figure 15 shows such an example, where we select two points in a 7 \times 7 grid (because the feature map extracted by our backbone is spatially 7 \times 7) of the first image and show the actual (ground-truth) as well as the predicted epipolar lines in the other image.

5. Implementation details CO3D-Retrieve

For experiments with the CO3D-Retrieve benchmark, the global-retrieval-only model (R50 (trained) as described in Sec. 5.1) is trained for 50 epochs with the Adam optimizer and a learning rate that starts at 0.0001 and decays exponentially by a factor of 10 every 20 epochs. The Reranking Transformer head is trained on top of this trained global model, by either freezing or finetuning the global model, with or without the Epipolar Loss. When training without the Epipolar Loss, the model is trained using a SGD optimizer with an initial learning rate of 5 \times 10^{-5} decayed exponentially by a factor of 10 over 40 epochs. When training with the Epipolar Loss, the above procedure is fol-
6. mAP analysis with same category retrieval

We empirically observe that a majority of high-ranked (i.e. top-5) false positives are images from the same category. We conduct an experiment where we compute the mAP while ranking only the images from the same category as the query image and ignoring out-of-class images. As shown in Tab. 1, we get a higher mAP when retrieval is only performed on the same category images. This means there are confusing images from outside the categories, albeit a small fraction compared to intra-class.

Further per-category analysis with our method reveals that the top 5 categories with the highest proportions of intra-class false positives (in descending order) are banana, suitcase, laptop, keyboard, umbrella in CO3D-Retrieve dataset and fan, cabinet, mug, coffee maker, kettle in SOP [2].

7. Breakdown of $R@K$ based on fraction of overlapping pixels

The proposed CO3D-Retrieve benchmark includes large variations in viewing angle among images of the same instance. We conduct an analysis to understand how our proposed method performs under a range of pose variations. To do this, we first compute an “Overlap Score (OS)” for each instance using ground-truth point-clouds available in CO3D-Retrieve. Large pose-variations lead to a low OS. We divide the query-set into 10 bins uniformly between OS=0.2 to 0.8 and compute the $R@1$ for each bin. These limits of OS are chosen because there are very few (< 1%) instance with an OS beyond the [0.2, 0.8] range. Fig. 3 shows $R@1$ for our proposed method and RRT [4] with respect to the OS. We can see that the R@1 of our method drops by 5.5% from highest to lowest OS, while RRT [4] drops by 10.6%. In conclusion, our Epipolar Loss is useful in extreme viewpoint changes.

| Dataset Name | Same Category Retrieval | Full Dataset Retrieval |
|--------------|-------------------------|------------------------|
| CO3D-Retrieve | 52.03                   | 49.52                  |
| SOP [2]      | 38.61                   | 37.25                  |

Table 1. Comparison of mAP computed while ranking only the images from the same category as the query image.

8. High-resolution results

In our experiments throughout the paper, the local features tensor obtained from Resnet50 backbone has a spatial resolution of 7×7. We train another transformer model with $L_{\text{EPI}}$ on input images of size 448×448 so that we obtain 14×14 local features. By doing this, we can obtain higher resolution (14×14×14×14) cross-attention maps, as shown in Fig. 16. Tab. 2 shows the performance achieved by the high resolution transformer model.

| Model       | Local features resolution | R@1 | R@10 | R@50 |
|-------------|---------------------------|-----|------|------|
| Original    | 7×7                       | 90.57 | 97.33 | 98.10 |
| High-res    | 14×14                     | 90.71 | 97.42 | 98.15 |

Table 2. Comparison with transformer model trained on 448×448 images. Both models are trained with $L_{\text{EPI}}$. “Original” corresponds to the result in Table 1 of main paper.

9. Failure Cases

It is important to look at the cases where our proposed method fails to retrieve good matches and analyze them for further improvement. Figures 17 and 18 show a few such examples for CO3D-Retrieve and SOP [2] respectively. We see that a common failure scenario for our method is when the query image is a close-up of the object (Fig. 17 (c,d) and Fig. 18 (c,d)) or repetitive patterns in objects such as keyboards (Fig. 17 (d)). A critical future direction for our work is to make the model robust to these scenarios.
10. Quality of Epipolar Geometry with LoFTR/MAGSAC++ method

During training, when the ground-truth epipolar geometry is not available, we use a pseudo-geometry predicted using a pretrained LoFTR [3] model for matching and MAGSAC++ [1] for robust optimization. The quality of the predicted epipolar geometry depends on the quality and number of matches obtained by the LoFTR model. In Figure 19, we show two examples demonstrating the success and failure cases of this method.

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Figure 4. CO3D-Retrieve: Example 1.

Figure 5. CO3D-Retrieve: Example 2.

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