

Rotationally Invariant Descriptors using Intensity Order Pooling Supplemental Material

Bin Fan, *Member, IEEE*, Fuchao Wu and Zhanyi Hu

The Authors are with the National Laboratory of Pattern Recognition, Institute of Automation, Chinese Academy of Sciences.



Fig. 1. Images of five types of scenes that are used for analysing orientation estimation errors in Section III.

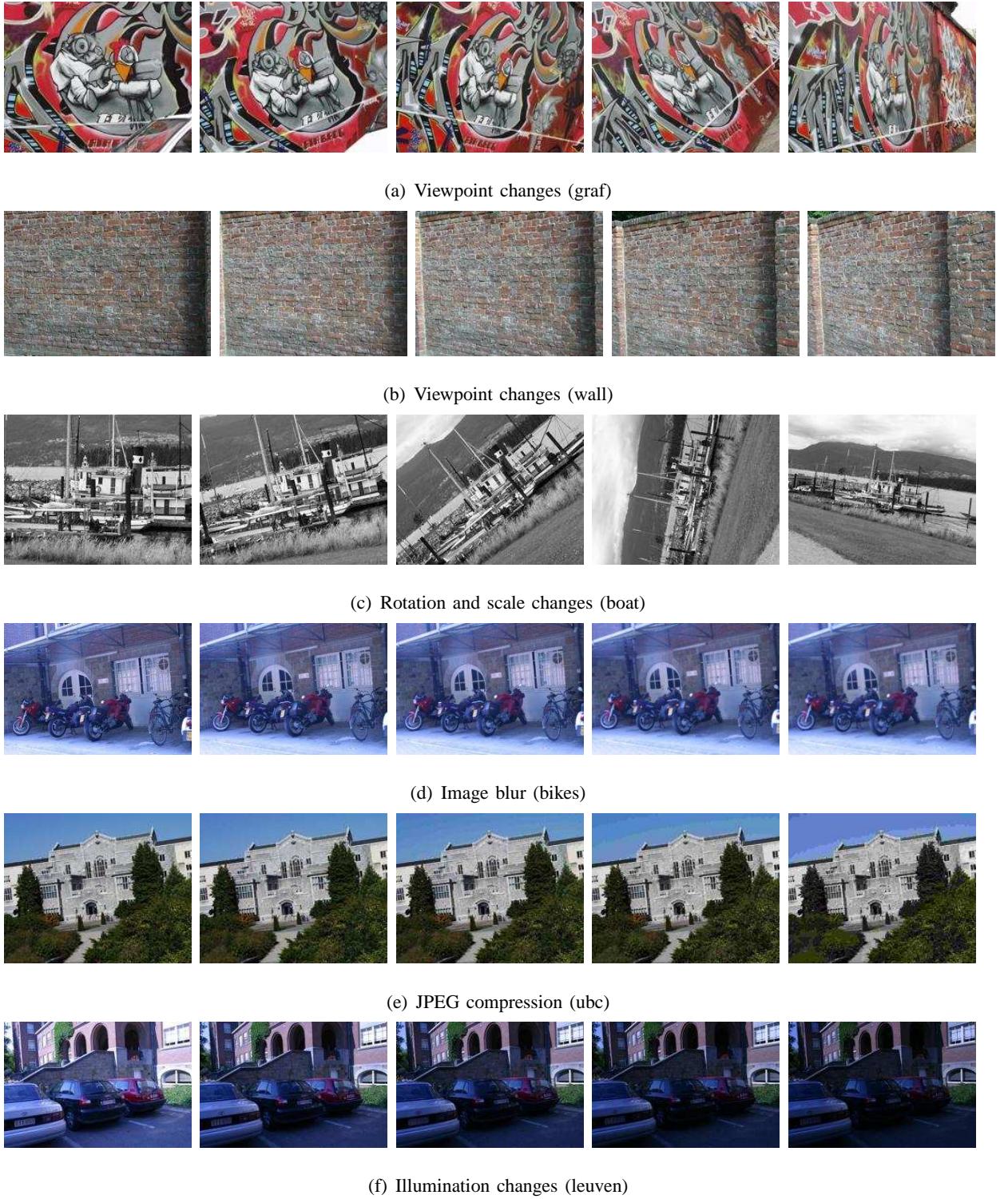


Fig. 2. Images in the Oxford dataset used in our experiments.

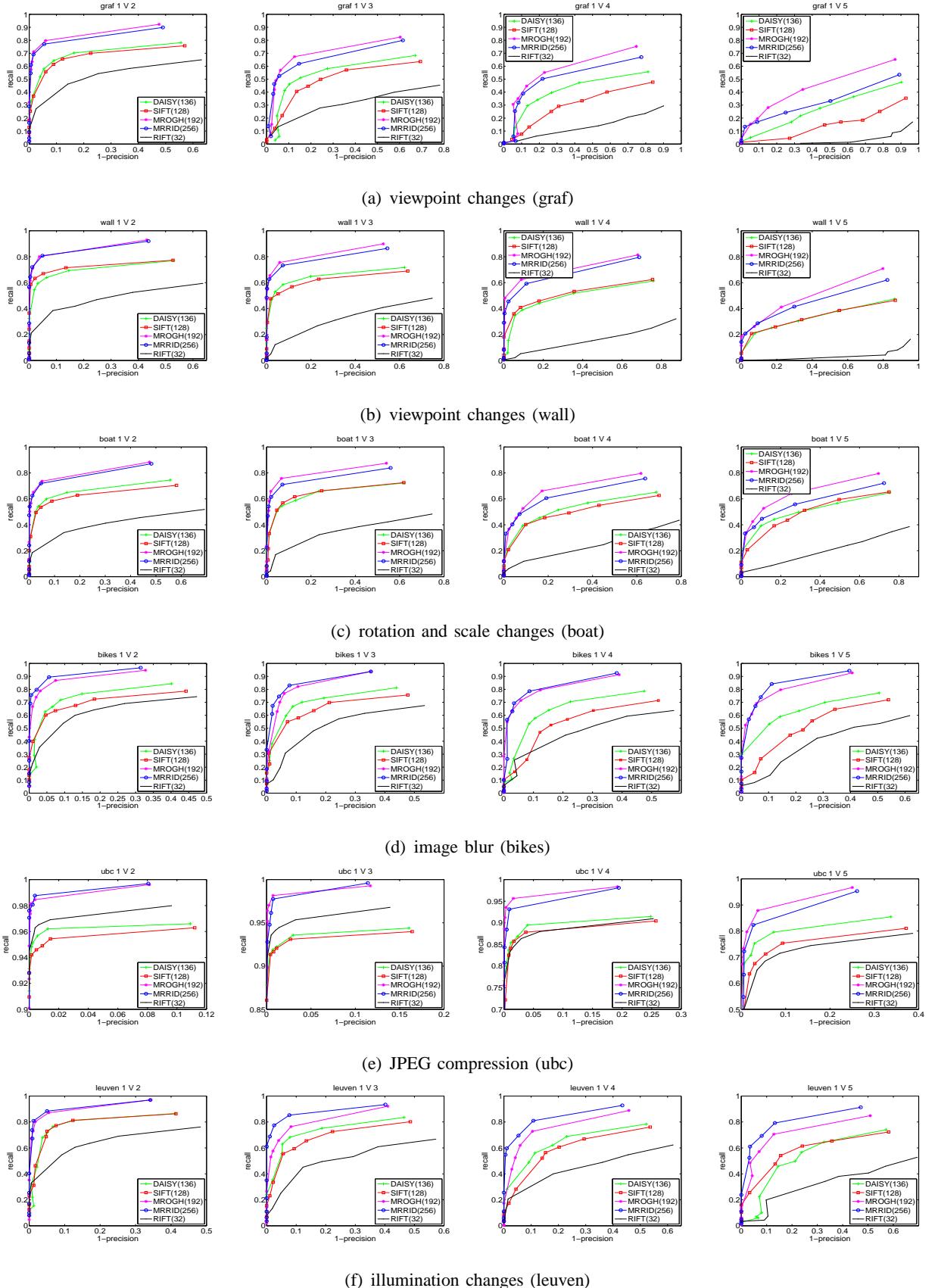


Fig. 3. Experimental results under various image transformations in the Oxford dataset for Harris-Affine Region.

November 24, 2011

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Fig. 4. (a) 20 of 53 objects in the first dataset (53 Objects) used for object recognition; (b) 20 of 201 buildings in the second dataset (ZuBuD) used for object recognition; (c) 20 of 1000 objects in the third dataset (Kentucky) used for object recognition.

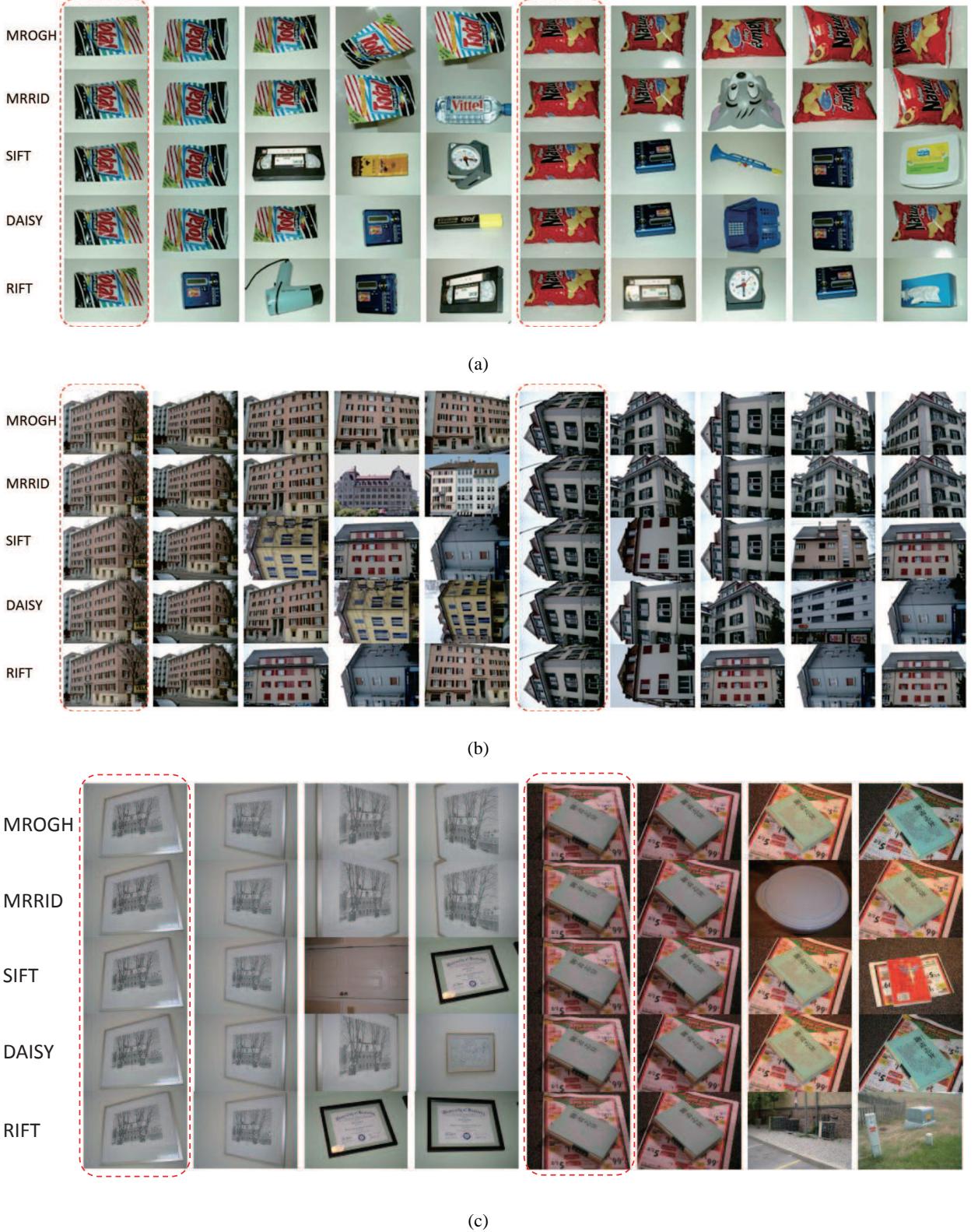


Fig. 5. Recognition results of (a) images in the dataset of 53 Objects, (b) images in the ZuBuD dataset and (c) images in the Kentucky dataset. The images in the red dash blocks are query images.