

Amodal Segmentation through Out-of-Task and Out-of-Distribution Generalization with a Bayesian Model

Supplementary Material

1. Compositional Spatial Priors Visualization

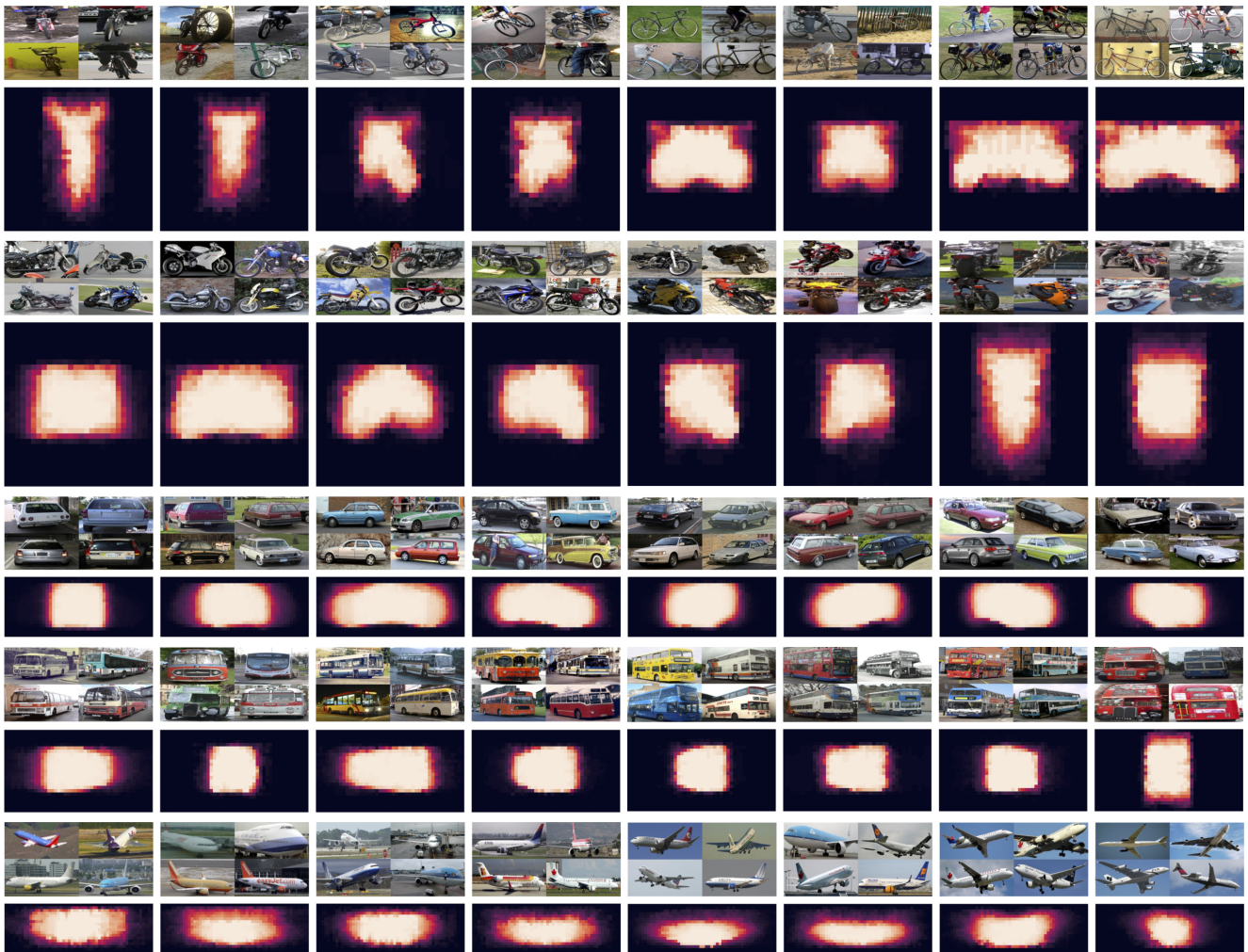


Figure 1: Additional Compositional Spatial Priors Visualizations. $M = 8$ spatial priors belonging to the bicycle, motorbike, car, bus, and aeroplane class are shown. Each prior $P(\vec{w}|y, m)$ is displayed below the examples of its corresponding learned objects.

2. Failure Cases

Please refer to Figure 2 for examples of failure cases in the predictions of amodal segmentation. In the first example, since the object background is composed of additional highly similar objects, the model failed to correctly predict the object's visible boundary, thus causing an incorrect prediction of the amodal mask. In the second example, since the object's pose is not observed during training, none of the trained poses can be used to correctly predict the occluded region of the object.

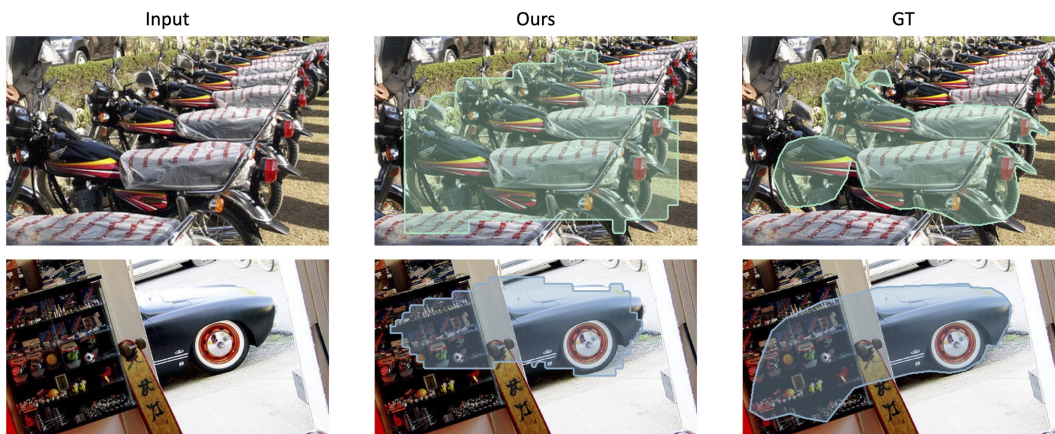


Figure 2: Failure cases visualizations.