

# Supplementary Material: UmeTrack: Unified multi-view end-to-end hand tracking for VR

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Table 1. Architecture table

Module	Input	Output	Hidden state	Layers
Encoder	$1 \times 96 \times 96$	$72 \times 6 \times 6$	NA	resnet + Conv11
Multi-view fusion	$144 \times 6 \times 6$	$72 \times 6 \times 6$	NA	(Conv11 + ReLU) $\times 2$ + Conv11
Temporal module	$72 \times 6 \times 6$	$72 \times 6 \times 6$	$18 \times 6 \times 6$	(Conv11 + ReLU) $\times 2$ + Conv11
Skeleton encoder	120	$4 \times 6 \times 6$	NA	linear + reshape
Regressor-K	$76 \times 6 \times 6$	41	NA	residual blocks $\times 2$ + Pool
Regressor-U	$72 \times 6 \times 6$	42	NA	residual blocks $\times 2$ + Pool

## A NETWORK ARCHITECTURE DETAILS

The input shape, output shape, hidden state shape and the layers used for each module are shown in Table 1. The encoder uses the same resnet as [Han et al. 2020] to ensure fair comparisons. The last layer of the encoder is a  $1 \times 1$  convolution layer for dimensionality reduction purpose. Multi-view fusion uses multiple  $1 \times 1$  convolutions and ReLU layers. Each  $1 \times 1$  convolution serves the purpose of feature fusion and dimensionality reduction. The output shape of the multi-view fusion module is the same as the output shape of the encoder. The temporal module is a recurrent neural network with a hidden state using  $1 \times 1$  convolution and ReLU as the building blocks. Both Regressor-K and Regressor-U are built from residual blocks. The output of Regressor-K contains 20 dimensional joint angles and 21 dimensional root point coordinates. Regressor-U outputs a 1 dimensional hand scale parameter in addition to joint angle and root point outputs.

For root transform prediction, we pre-define 7 points for representing a transformation in the hand local space:  $v_H = \{[0, 0, 0]^T, [1, 0, 0]^T, [0, 1, 0]^T, [0, 0, 1]^T, [1, 1, 0]^T, [1, 0, 1]^T, [0, 1, 1]^T\}$ . And the task of a regressor is to predict the location of these points denoted as  $\hat{v}$  in the reference camera space. The root transformation can be recovered using Singular Value Decomposition [Sorkine-Hornung and Rabinovich 2016] by solving the following equation:

$$\hat{T}_H = \min_{\hat{T}_H} \sum_i \|\hat{T}_H * v_{H,i} - \hat{v}_i\|_2^2 \quad (1)$$

## REFERENCES

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