

Supplementary Material

Dynamic Filter Networks

1 Video Prediction

In this section, we add more results of the experiments on the moving MNIST and highway driving datasets. We added an animated gif-file for every sequence we show here.

1.1 Moving MNIST

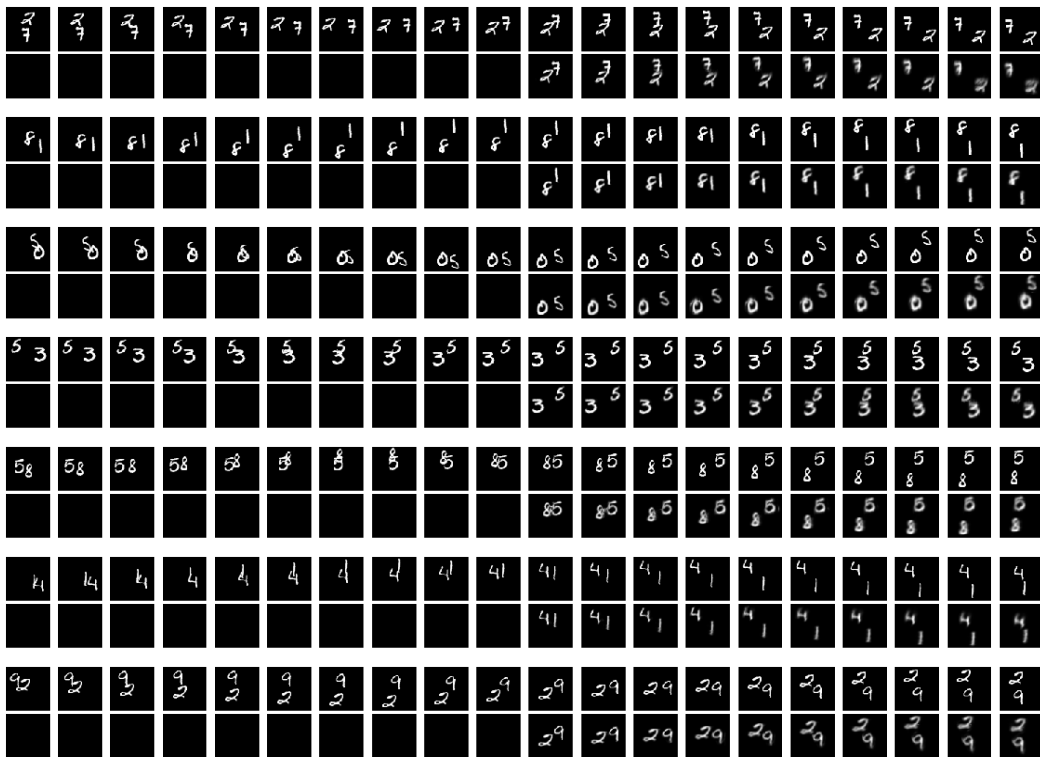


Figure 1: Results on moving MNIST dataset with 2 moving digits. In the first row, the left half are input sequence and the right half are ground truth of the future frames; in the second row, the right half is the prediction of our model.

We visualize the dynamically generated filter for the first predicted frame.

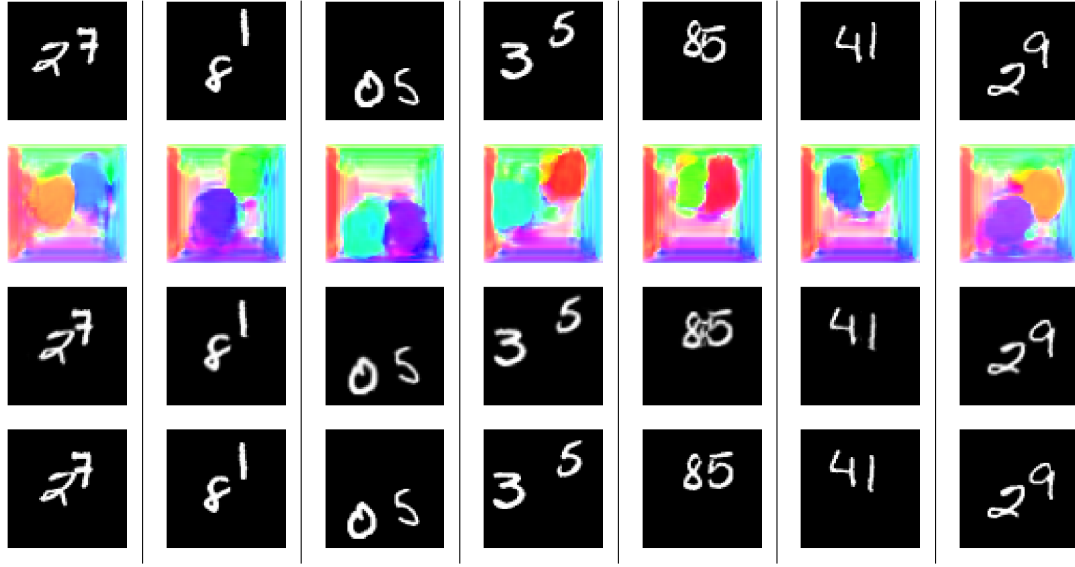


Figure 2: Visualization of the dynamically generated filters. The first row are the previous frame, the second row are the visualization of filters, the third row are our prediction of the current frame and the fourth row are the ground truth.

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- 6 We also run the model which is trained on 2 moving digits on out-of-domain data which has 1 moving digit or 3 moving digits. It shows the model has good generalization ability.

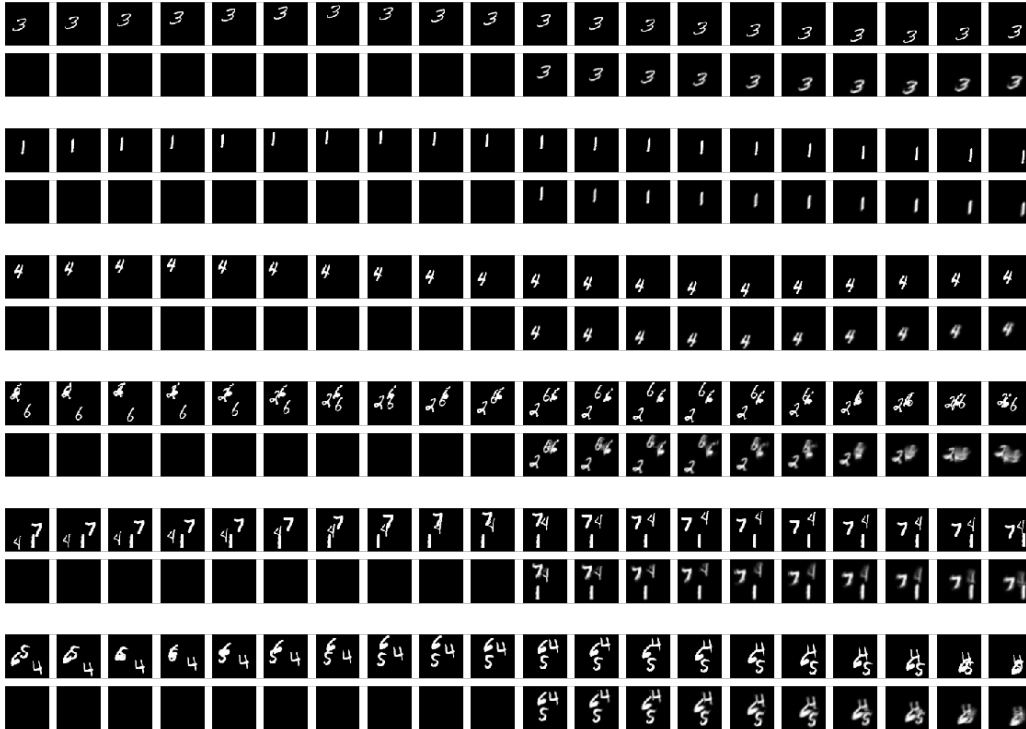


Figure 3: Results of out-of-domain input experiment with 1 moving digit and 3 moving digits.

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8 1.2 Highway driving

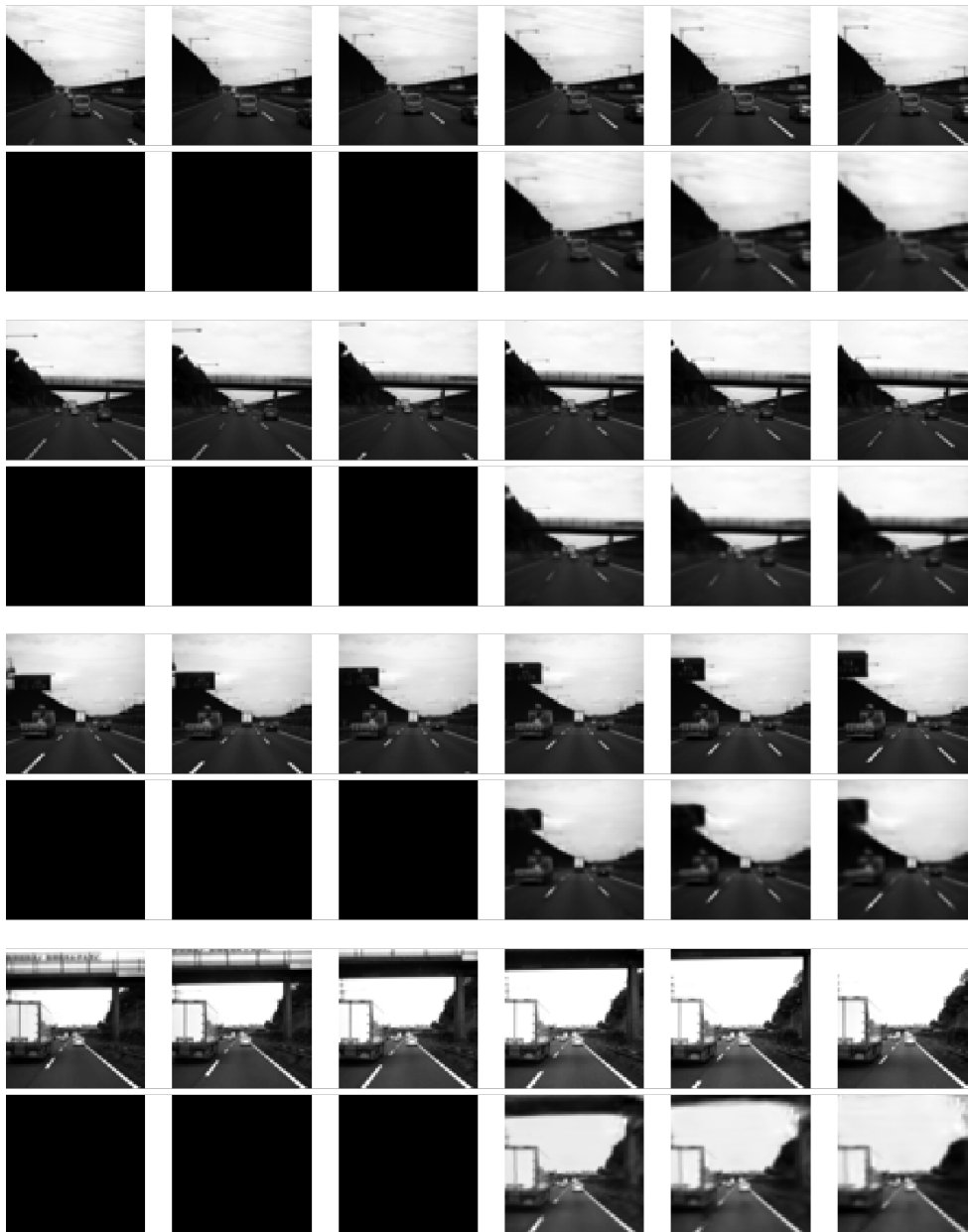


Figure 4: Results on highway driving dataset.

9 **2 Stereo Prediction**

10 We make a video of stereo prediction results for the whole test sequence. In each frame, the first one
11 is the left view image, the second one is the visualization of filters, the third one is our prediction of
12 the right view, and the last one is the groundtruth.