DEPTH-AWARE SCORING AND HIERARCHICAL ALIGNMENT FOR MULTIPLE OBJECT TRACKING

Supplementary Material

1. BENCHMARK EVALUATION ON MOT17 AND MOT20

Main performance metrics for MOT are HOTA, IDF1, and AssA [1]. HOTA assesses both detection and association accuracy. IDF1 and AssA primarily evaluate association performance, while MOTA is predominantly focused on detection accuracy. In our results tables, ↑means the higher, the better, and ↓means the lower, the better. Bold numbers indicate the best performance. We adopt YOLOX [2] as the default object detector. In our results tables, MOT methods that also use YOLOX as the detector are highlighted in blue.

MOT17 and MOT20 are well-established pedestrian tracking benchmarks characterized by relatively linear motion patterns compared to DanceTrack and SportsMOT having non-linear motion. MOT17 consists of urban scenes with moderate crowd density and occasional occlusions, while MOT20 presents highly crowded environments. These datasets are widely used for evaluating tracking performance in dense, urban scenarios with largely predictable pedestrian trajectories. However, their focus on objects with temporally consistent orientations relative to the camera differs from the dynamic, non-linear motion patterns that DepthMOT is optimized for. We evaluate DepthMOT on MOT17 and MOT20 under the *private* detection protocol, as shown in Table 1.

As seen in Table 1, trackers based on linear motion models, such as CMTrack [3], MotionTrack [4], and Deep OC-SORT [5], excel in MOT17 and MOT20 due to the predictable pedestrian trajectories. In contrast, DiffMOT and our DepthMOT perform better in more dynamic scenarios like DanceTrack and SportsMOT. Both non-linear models face challenges in MOT17 and MOT20, where linear motion models tend to be more effective.

Additionally, as illustrated in Fig. 1, zero-shot depth estimation encounters challenges in low-light conditions, producing low-contrast depth maps that make it difficult to distinguish distant objects. This limitation affects the accuracy of DepthMOT on MOT17 and MOT20. Despite these challenges, DepthMOT achieves the lowest false positive (FP) rate of 1.3, demonstrating the effectiveness of HAS in reducing false associations and track fragmentation.

While DepthMOT is not explicitly trained on each MOT dataset, it still performs competitively in high-occlusion environments and showcases strong adaptability across diverse tracking scenarios.

MOT17									
Tracker	**HOTA↑**	**MOTA↑**	**IDF1↑**	**FP(10^4)↓**	**FN(10^4)↓**	**ID$_s$↓**	**Frag↓**	**AssA↑**	**AssR↑**
FairMOT [6]	59.3	73.7	72.3	2.75	11.7	3,303	8,073	58.0	63.6
TransTrack [7]	54.1	75.2	63.5	5.02	8.64	3,603	4,872	47.9	57.1
MOTR [8]	57.2	71.9	68.4	2.11	13.6	2,115	3,897	55.8	59.2
CenterTrack [9]	52.2	67.8	64.7	1.8	1.6	3,039	-	-	-
MeMOTR [10]	58.8	72.8	71.5	-	-	-	-	58.4	-
DiffusionTrack [11]	60.8	77.9	73.8	-	-	3,819	4,815	58.8	-
MixSort-OC [12]	63.4	78.9	77.8	-	-	1,509	-	63.2	-
MixSort-Byte [12]	64.0	78.9	78.7	-	-	2,235	-	64.2	-
C-BIoU [13]	64.1	81.1	79.7	-	-	-	-	63.7	-
GHOST [14]	62.8	78.7	77.1	-	-	2,325	-	-	-
ByteTrack [15]	63.1	80.3	77.3	2.55	8.37	2,196	2,277	62.0	68.2
OC-SORT [16]	63.2	78.0	77.5	1.51	10.8	1,950	2,040	63.2	67.5
StrongSORT [17]	63.5	78.3	78.5	-	-	1,446	-	63.7	-
GeneralTrack [18]	64.0	80.6	78.3	-	-	1,563	-	63.1	-
StrongSORT++ [17]	64.4	79.6	79.5	2.79	8.62	1,194	1,866	64.4	**71.0**
Deep OC-SORT [5]	64.9	79.4	80.6	1.66	9.88	1,023	2,196	65.9	70.1
MotionTrack [4]	65.1	**81.1**	80.1	2.38	**8.16**	1,140	-	-	-
CMTrack [3]	**65.5**	80.7	**81.5**	2.59	8.19	**912**	**1,653**	**66.1**	-
*DiffMOT [19]	64.5	79.8	79.3	-	-	-	-	64.6	-
*DepthMOT	62.7	76.5	77.9	**1.3**	11.7	1,342	-	63.6	68.8
MOT20									
Tracker	**HOTA↑**	**MOTA↑**	**IDF1↑**	**FP(10^4)↓**	**FN(10^4)↓**	**ID$_s$↓**	**Frag↓**	**AssA↑**	**AssR↑**
FairMOT [6]	54.6	61.8	67.3	10.3	8.89	5,243	7,874	54.7	60.7
DiffusionTrack [11]	55.3	72.8	66.3	-	-	4,117	4,446	51.3	-
GHOST [14]	61.2	73.7	75.2	-	-	1,264	-	-	-
ByteTrack [15]	61.3	77.8	75.2	2.62	8.76	1,223	1,460	59.6	66.2
GeneralTrack [18]	61.4	77.2	74.0	-	-	1,627	-	59.5	-
StrongSORT [17]	61.5	72.2	75.9	-	-	1,066	-	63.2	-
OC-SORT [16]	62.1	75.5	75.9	1.80	10.8	913	1,198	62.0	67.5
StrongSORT++ [17]	62.6	73.8	77.0	1.66	11.8	770	1,003	64.0	69.6
MotionTrack [4]	62.8	78.0	76.5	2.86	**8.41**	1,165	1,321	61.8	-
Deep OC-SORT [5]	63.9	75.6	79.2	1.69	10.8	779	1,536	65.7	**70.8**
CMTrack [3]	**64.8**	76.2	**79.9**	2.22	10.04	**730**	**987**	**66.7**	-
*DiffMOT [19]	61.7	**76.7**	74.9	-	-	-	-	60.5	-
*DepthMOT	62.4	73.2	77.3	**1.3**	12	1,141	-	64.3	68.6

Table 1. **Results on MOT17-test and MOT20-test.** Methods in the blue blocks use the same YOLOX detector. The methods with * indicate that they are non-linear models. As can be seen, no tracker performs best across metrics and datasets. Our DepthMOT has the lowest false positive (FP).

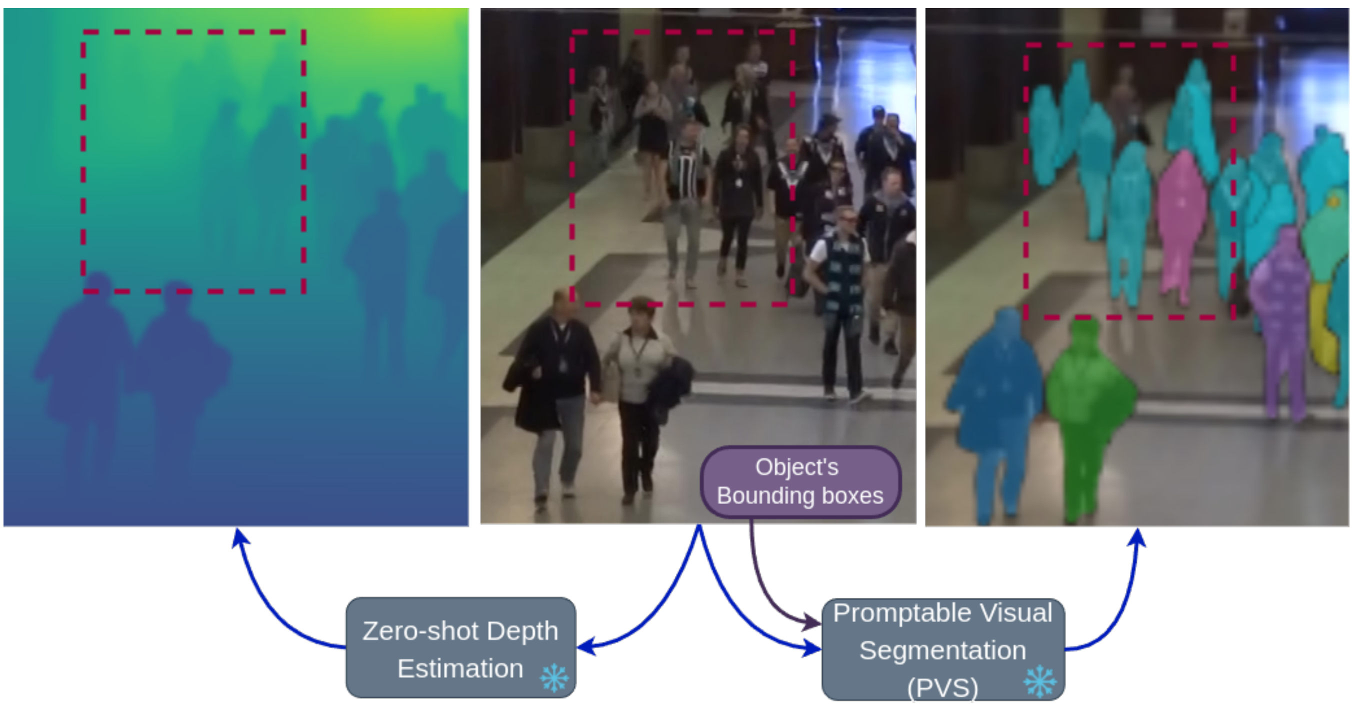

Fig. 1. **Challenges.** An example of zero-shot depth estimation and PVS modules, emphasizing the encountered challenges under different lighting conditions in the MOT20 dataset. The highlighted area, marked by a dotted square, illustrates that the depth map of certain objects is not accurately predicted.

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