

Unseen Object Pose Estimation via Registration

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- Current object pose estimation methods mostly rely on instance specific features, which limits their ability to generalize to unseen objects.
- 3D geometrical construction is embedded in observation, yet commonly neglected.
- We reconstruct full model and view model from reference and query observation, then seek for probabilistic correspondence between them to solve registration problem.
- Our method achieves comparable performance with SOTA, with accuracy and efficiency

