The goal of this paper is to estimate the 6D pose and dimensions of unseen object instances in an RGB-D image. Contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary to "instance-level" 6D pose estimate the following the contrary the	timatio