DLM-Semesterprojekt 2019

Vorlesung DLM

Rahmenbedingungen

- 2.12.2019: Projektlabor
- 9.12.2019: Projektlabor
- 16.12.2019: Projektlabor
- 13.12.2019: Projektlabor
- 4.01.2020: Abgabe des Berichts
- 4.01.2020: 10:45 – 12:45 Uhr (L112)

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- Bestimmen der 3D-Boundingbox eines Roboters

- Literatur
  - Tremblay, Jonathan, et al. "Deep object pose estimation for semantic robotic grasping of household objects." *arXiv preprint arXiv:1809.10790* (2018).

  - Tekin, Bugra, Sudipta N. Sinha, and Pascal Fua. "Real-time seamless single shot 6d object pose prediction." *Proceedings of the IEEE Conference on Computer Vision and Pattern Recognition*. 2018.
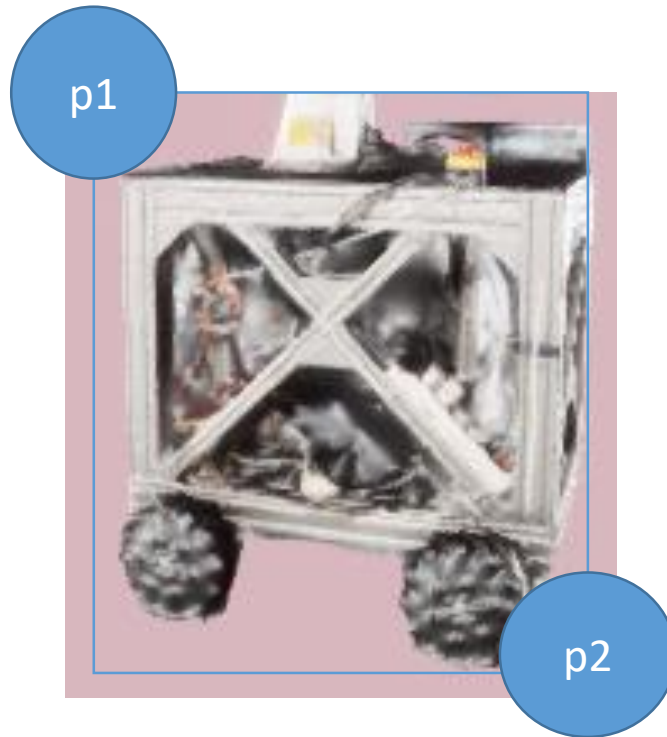
Corner IDs of the Cuboid

0

0

1

1

5

6

1

2

8

7

4

3
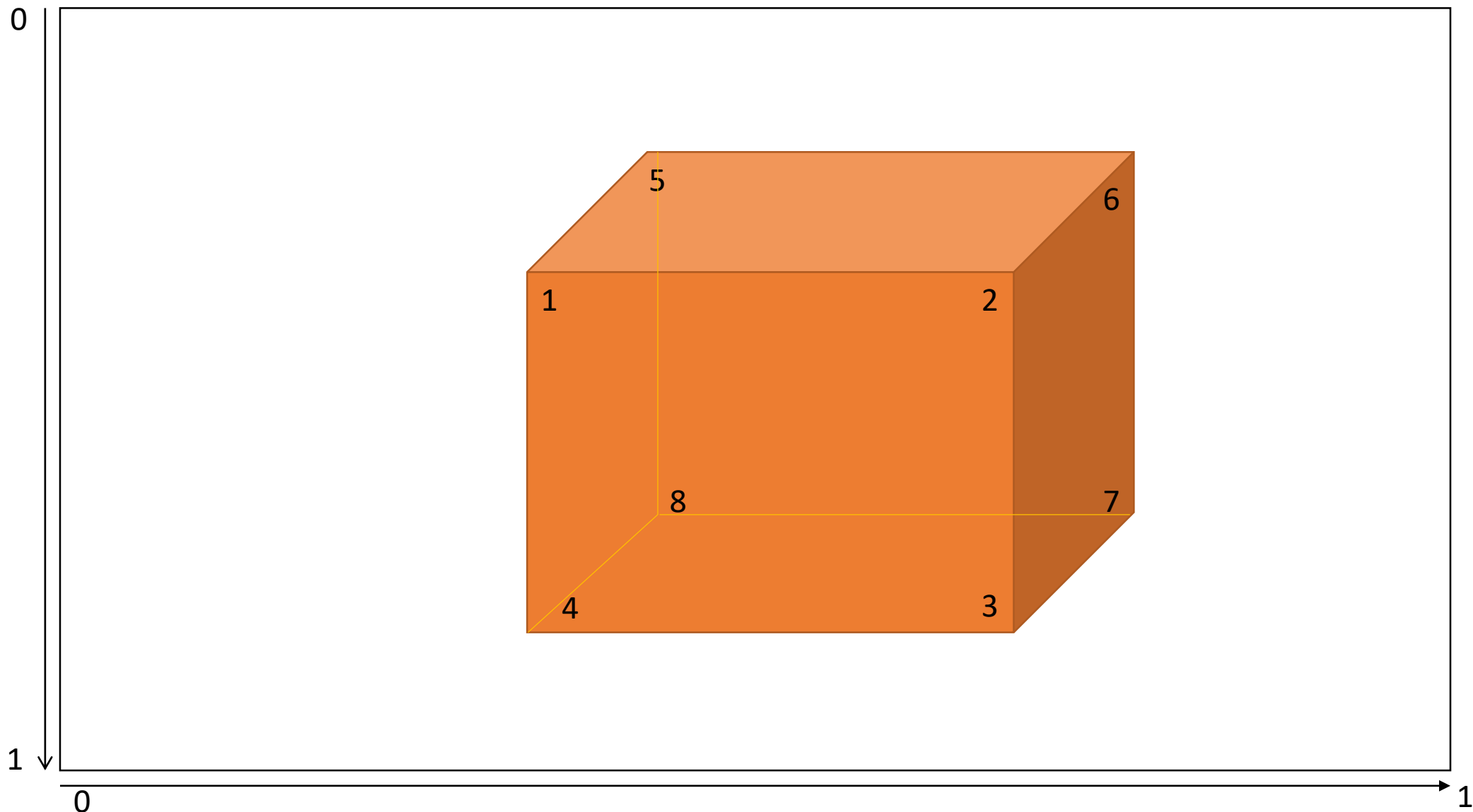
Corner IDs of the Cuboid (3D)
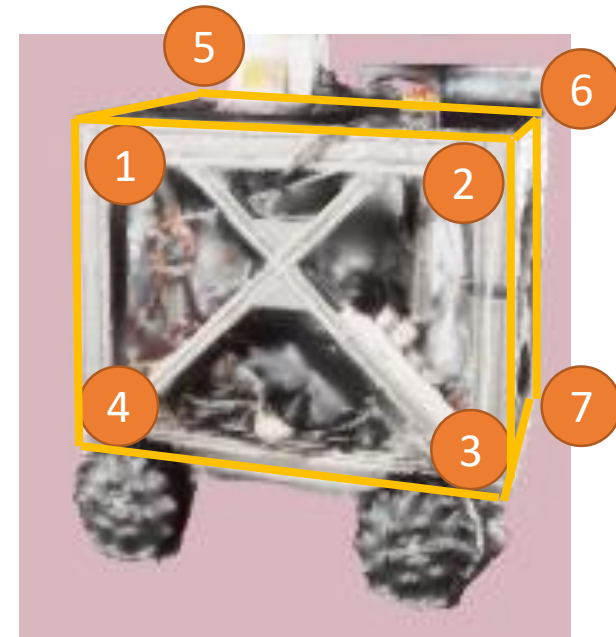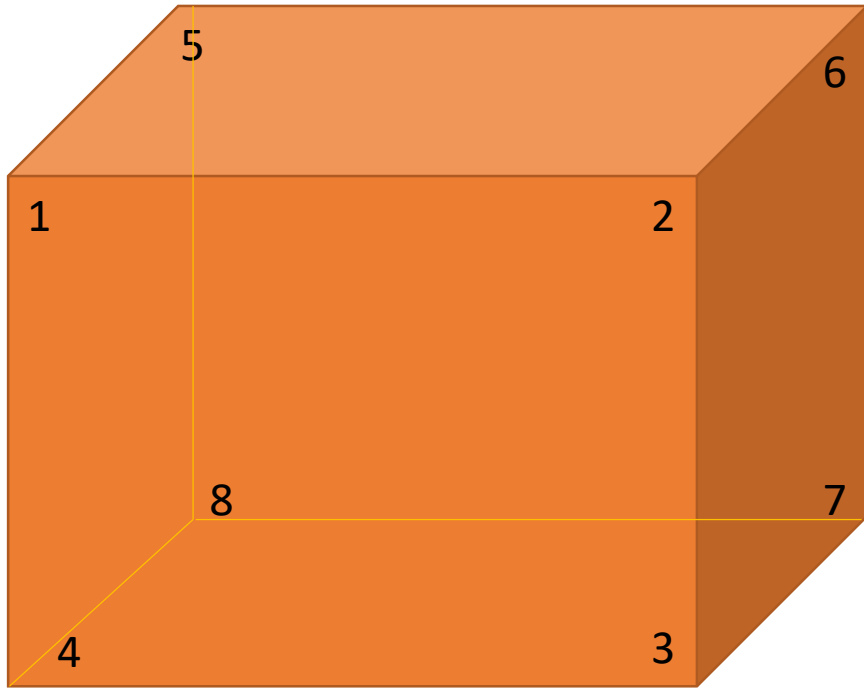
Corner IDs of the Cuboid (3D)

Source and Target DataFormat

Bilddaten: png-Bilddatenformat

Target: Json-Text-Format

Zusammenhang zwischen Bilddaten und Target:
image00001.png, image00001.json

```
{

        "class": "ESMRoboter",

        "3dBoundingBox": [ x1 y1 x2 y2 x3 y3 x4 y4 x5 y5 x6 y6 x7 y7 x8 y8 ],

        "2dBoundingBox": [ px1 py1  px2 py2 ]

}
```

Verzeichnisse

- D: data/dlmWS19/project/synthetic
- D: data/dlmWS19/project/scan
- D: data/dlmWS19/project/real