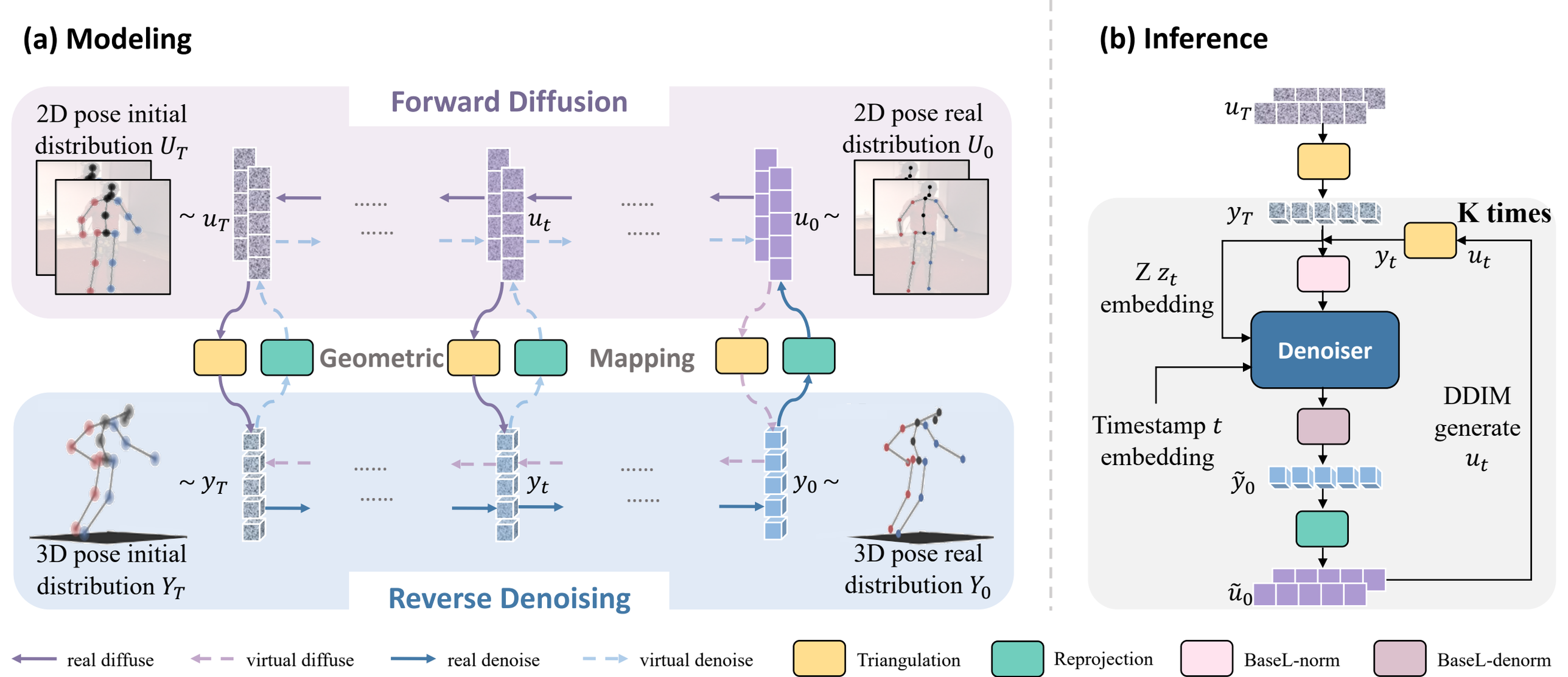
(a) Modeling
Forward Diffusion
2D pose initial distribution U_T
$\sim u_T$
u_t
$u_0 \sim$
2D pose real distribution U_0
Geometric
Mapping
$\sim y_T$
y_t
$y_0 \sim$
3D pose initial distribution Y_T
3D pose real distribution Y_0
Reverse Denoising
(b) Inference
u_T
y_T
K times
y_t
u_t
Z z_t embedding
Denoiser
Timestamp t embedding
DDIM generate u_t
$\tilde{y}_0$
$\tilde{u}_0$
real diffuse
virtual diffuse
real denoise
virtual denoise
Triangulation
Reprojection
BaseL-norm
BaseL-denorm