



INTRODUCTION

The need for the existence of accurate 3D mesh models has increased dramatically in recent years, in part due to the advances in generative approaches [1,2]. becoming models are Such necessary priors for grasping and manipulation tasks [3,4]. However, designing such objects from scratch is challenging endeavor. With these goals in mind, we propose GemSketch as a tool designed for extracting the models of generalized 3D cylinders and cuboids. GemSketch can estimate models from partial and occluded observations of single or multiple-view point clouds.



RESULTS

We extracted 16 different objects from the BigBIRD [5] dataset and compared performed a qualitative as well as a quantitative comparison between out extracted models and the ground truths in the data set. GemSketch can leverage the availability of multiple-view point clouds and images of objects. Consequently, some objects were extracted with more than a single view.

Two metrics were used for quantitative comparison. Hausdorff distance was used to measure the dissimilarity of each object with its ground truth. Additionally, we computed the ICP errors of the alignment between each extracted model and its ground truth. We achieved a mean normalized Hausdorff distance of 5.66%.





METHODOLOGY



Point Cloud **Contour Sketch**

Profile and Spline Extraction Followed by Profile Propagation

Extracted mesh

After drawing the contour, copies of the estimated profile (cap) of the object are created along the object's spine to create the final 3D model.







The table below outlines the results of comparison of each object with its ground truth available in the BigBIRD [5] dataset.

Object Name	ICP Error (mm)	Hausdorff Distance (%)	Object Name	ICP Error (mm)	Hausdorff Distance (%)
3m_high_tack_spray_adhesive	6.20	3.40	expo_marker_red	3.89	6.95
advil_liqui_gels	8.04	6.50	haagen_dazs_butter_pecan	6.21	4.69
bai5_sumatra_dragonfruit	10.62	5.16	hunts_sauce	6.56	5.85
cheez_it_white_cheddar	8.78	5.94	krylon_crystal_clear	6.25	4.87
cholula_chipotle_hot_sauce	5.82	4.84	<pre>pop_secret_light_butter</pre>	9.42	6.37
coca_cola_glass_bottle	29.69	7.39	red_bull	6.10	4.57
coffee_mate_french_vanilla	5.59	4.63	red_cup	4.25	7.34
dove_beauty_cream_bar	6.67	6.67	v8_fusion_peach_mango	6.48	5.40

(a) Input image







(c) Models superimposed on the image

(d) Models superimposed on the point cloud

REFERENCES

[1] V. Narayanan and M. Likhachev, "Discriminatively-guided deliberative perception for pose estimation of multiple 3d object instances." in Robotics: Science and Systems, 2016. [2] J. Mahler, J. Liang, S. Niyaz, M. Laskey, R. Doan, X. Liu, J. A. Ojea, and K. Goldberg, "Dex-net 2.0: Deep learning to plan robust grasps with synthetic point clouds and analytic grasp metrics," arXiv preprint arXiv:1703.09312, 2017 [3] Z. Sui, L. Xiang, O. C. Jenkins, K. Desingh, "Goal-directed Robot Manipulation through Axiomatic Scene Estimation", International Journal of Robotics Research, in press, 2016. [4] K. Desingh, O. C. Jenkins, L. Reveret, Z. Sui. "Physically Plausible Scene Estimation for Manipulation in Clutter", in IEEE-RAS International Conference on Humanoid Robotics, 2016. [5] A. Singh, J. Sha, K. S. Narayan, T. Achim, and P. Abbeel, "Bigbird: A large-scale 3d database of object instances," in 2014 IEEE International Conference on Robotics and Automation (ICRA), May 2014, pp. 509–516.

731



