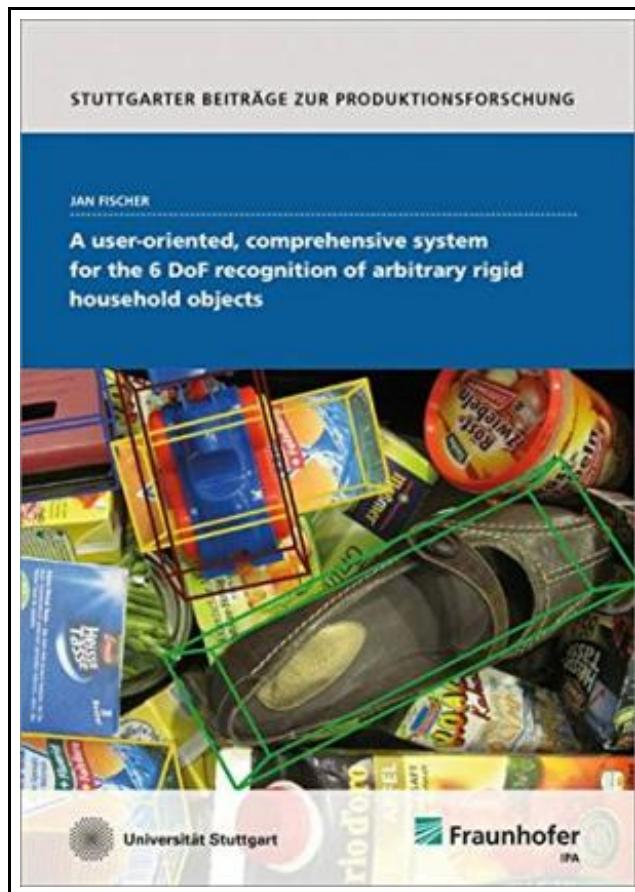


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Fraunhofer Verlag Okt 2015, 2015. Taschenbuch. Book Condition: Neu. 21x14.8x cm. Neuware - The objective of this thesis is the development of a model-based object recognition system for the 6 degrees of freedom localization of typical rigid household objects that explicitly enables an intuitive teaching of new objects. When considering the perceptual process of object recognition in its entirety, it may be divided into the three main areas: data acquisition, object modeling and object localization. The different areas are examined individually and distinct contributions to each of them are presented and evaluated. The originating conditions for the recognition process system are one-shot images of range and color data. Considering data acquisition, it is most often taken for granted that a sensor delivers directly 2.5D data or color information. However, when combining different sensor modalities, it is possible to exceed the data quality of a single sensor. The thesis follows this idea and presents a novel sensor fusion technique for data acquisition that combines the 2.5D input data from a stereo and a range imaging system. Regarding object modeling, the thesis presents a method for dense object modeling directly on the robot using its manipulator and camera system. Additionally, two stand-alone training setups are introduced which avoid the explicit need of a robotic manipulator for object modeling. One is using a turn table to rotate the object in front of the camera system and the other one is using a chessboard where the camera is manually moved around a stationary object. Initial work conducted within the scope of this thesis proposes a fastSLAM-based in-gripper object modeling approach which is able to cope with multi-occurrences of similar textures on the object's surface. This approach is further developed and the information filter is replaced by a bundle adjustment algorithm that enables a faster...

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