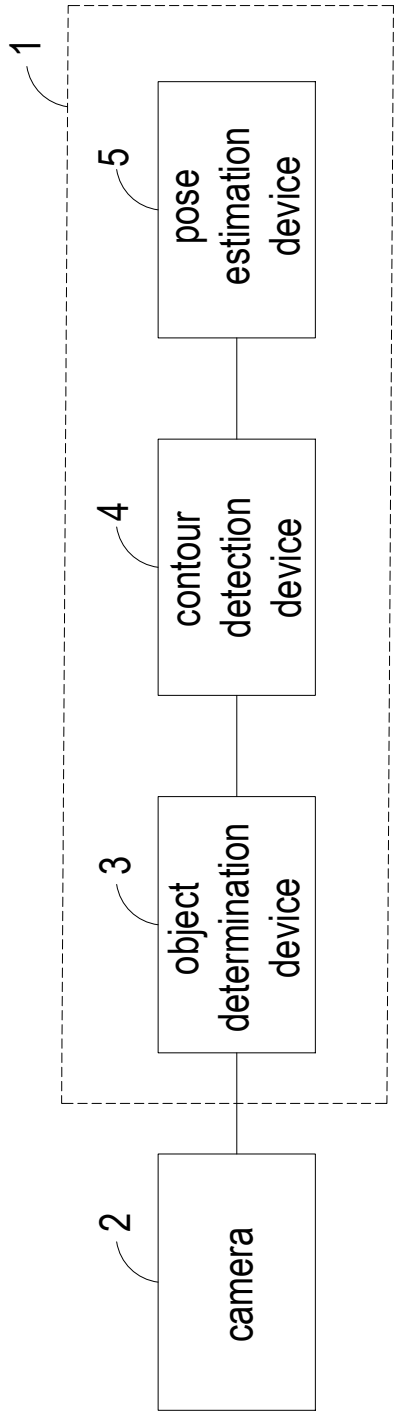
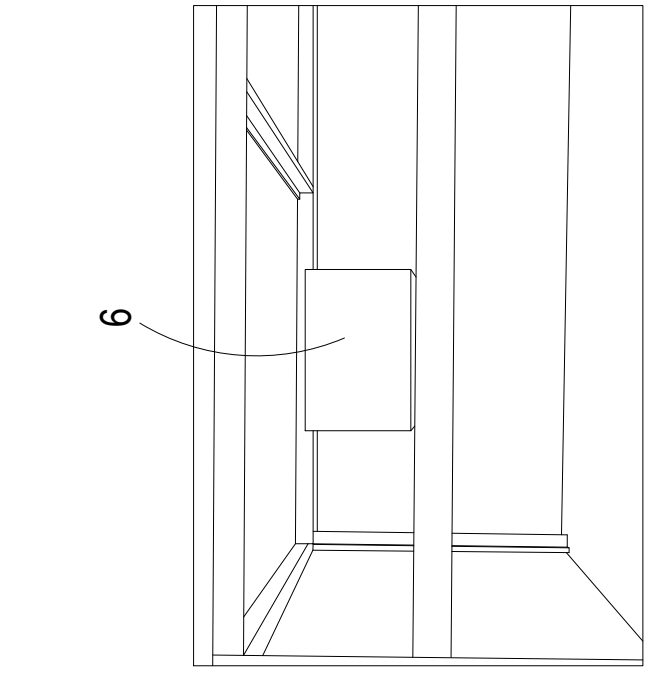

1
2
camera
3
object determination device
4
contour detection device
5
pose estimation device

FIG. 1



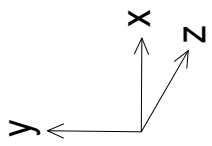


FIG. 2

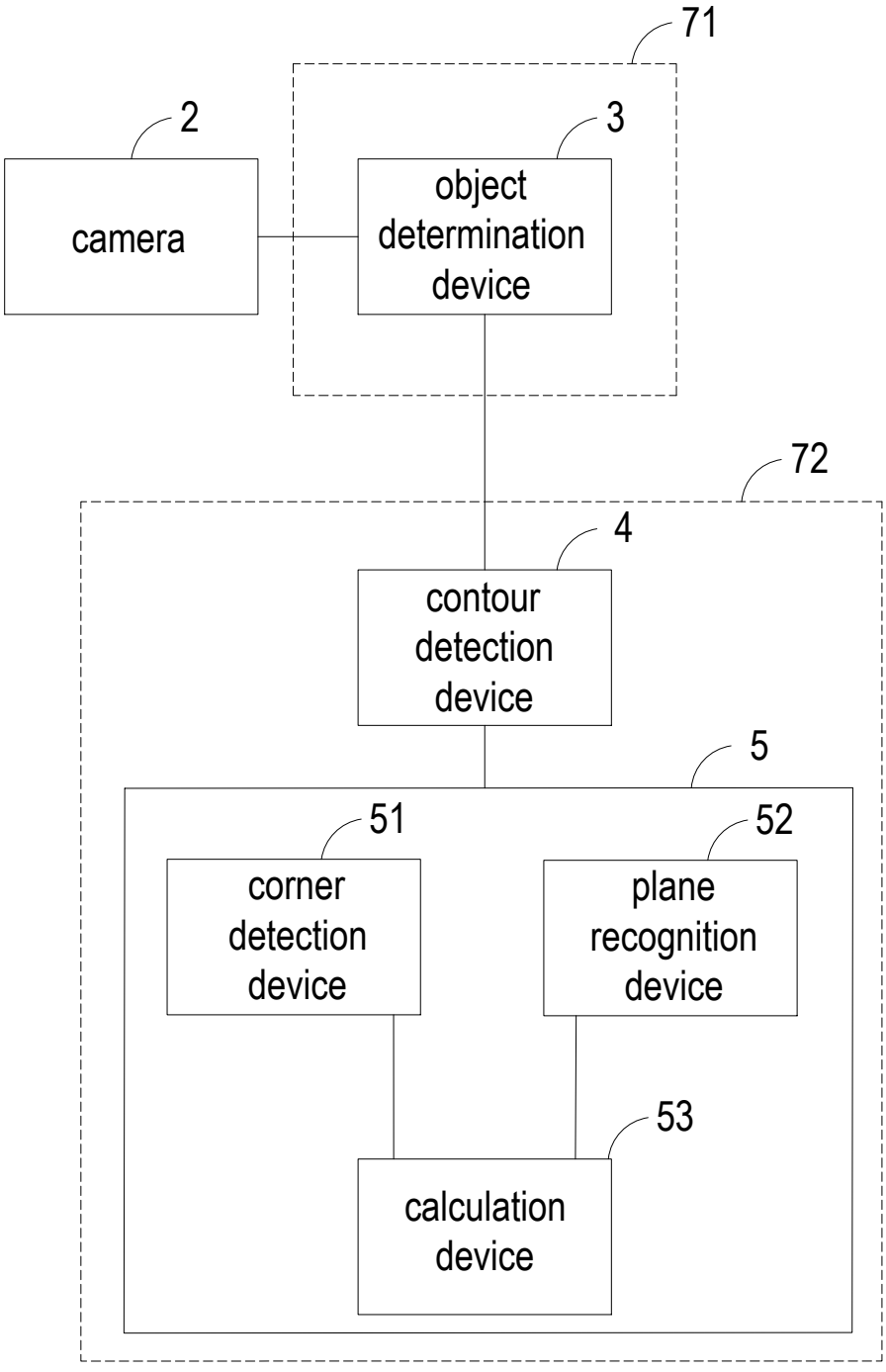

71
2
3
camera
object determination device
72
4
contour detection device
5
51
52
corner detection device
plane recognition device
53
calculation device

FIG. 3

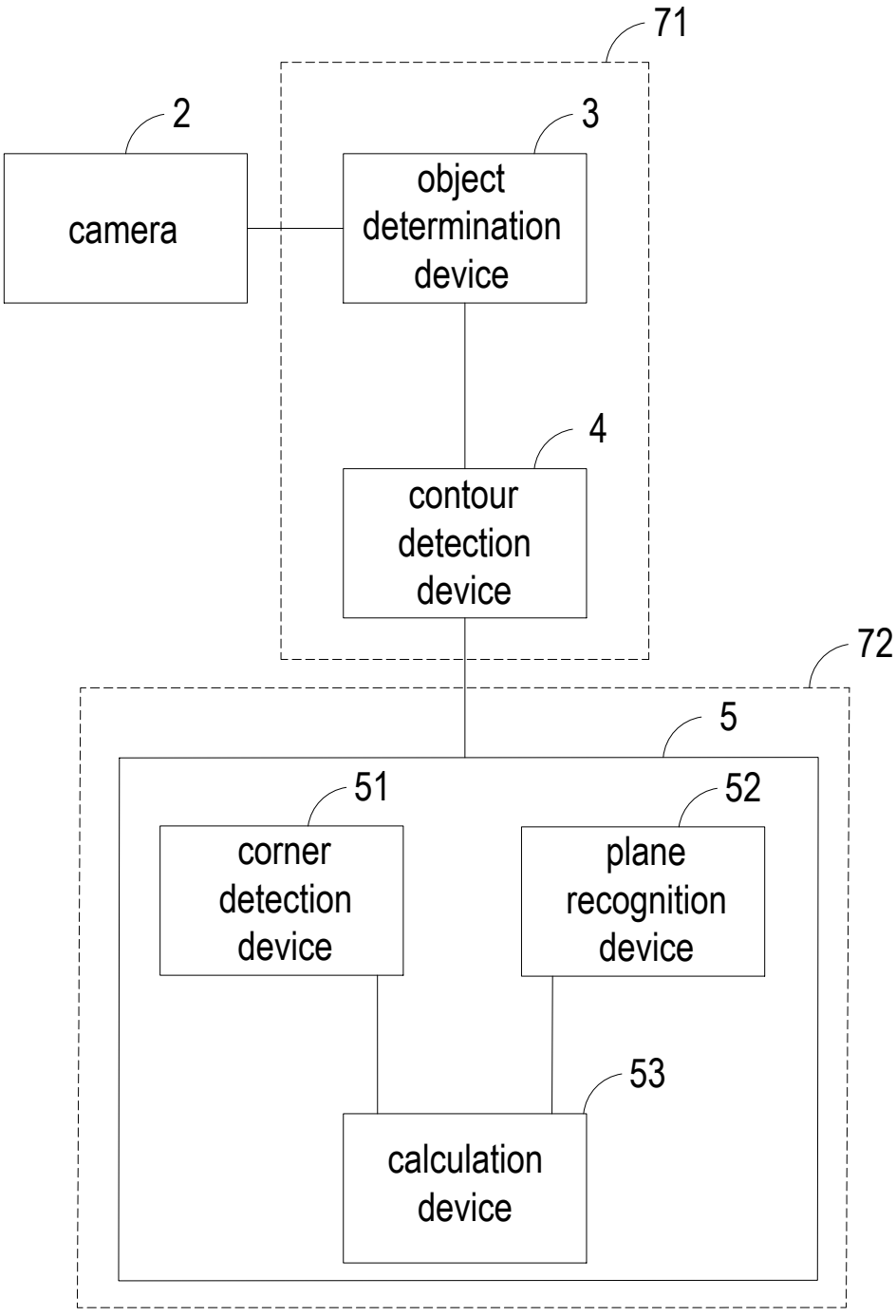

71
2
3
camera
object determination device
4
contour detection device
72
5
51
52
corner detection device
plane recognition device
53
calculation device

FIG. 4

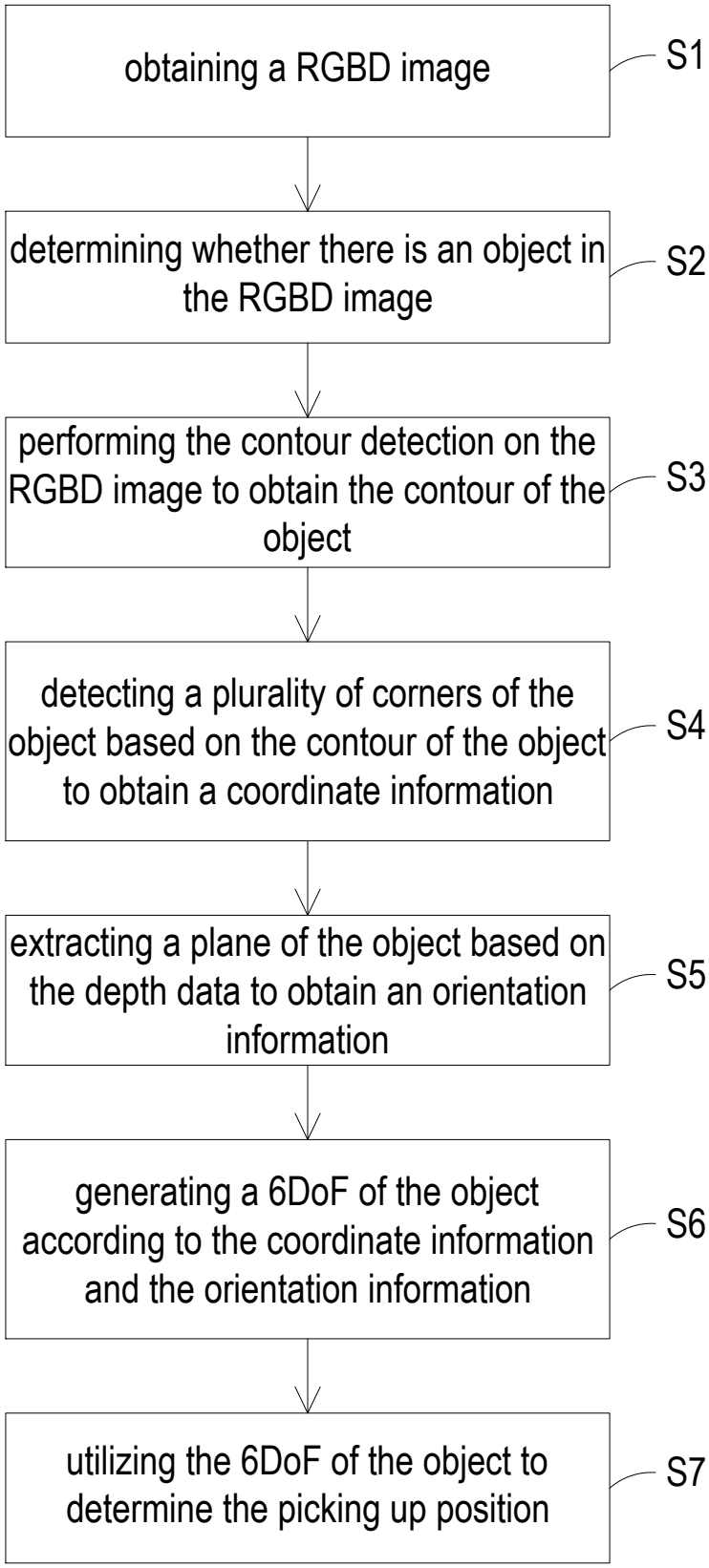

obtaining a RGBD image
S1
determining whether there is an object in the RGBD image
S2
performing the contour detection on the RGBD image to obtain the contour of the object
S3
detecting a plurality of corners of the object based on the contour of the object to obtain a coordinate information
S4
extracting a plane of the object based on the depth data to obtain an orientation information
S5
generating a 6DoF of the object according to the coordinate information and the orientation information
S6
utilizing the 6DoF of the object to determine the picking up position
S7

FIG. 5