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been conducted to test the ability of incorporating the knowledge of how human vision system works in a three-dimensional object recognition system. Firstly, the process of shape outline detection and secondly, the use of multiple viewpoints of object. Shape outline readings are put through normalization and dimensionality

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This study proposes a 3D object recognition and registration system for robotic grasping that uses a Kinect sensor. To ensure accurate pose estimation when an object is placed symmetrically in relation to the viewpoint, this study also proposes an MVFH descriptor that consists of two parts: a surface shape component that comprises an extended FPFH and an extended viewpoint direction component.

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Typically, such applications utilize sensor systems which allow for the generation of 3D data and perform matching in 3D space. Another way to determine the 3D pose of an object is to estimate the projection of the object location in 3D space onto a 2D camera image. ... “Three-Dimensional Object Recognition from Single Two-Dimensional Images ...

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The proposed object recognition system is composed of three stages: feature extraction, feature matching, and significance testing. For feature extraction, the conventional 2-D Gabor filtering^{27–29} is extended to 3-D space in order to analyze volume data. A Gabor feature is a multiresolution representation of object structure and energy in the spatial-frequency domain. Three-dimensional Gabor filtering-

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3D face recognition has the potential to achieve better accuracy than its 2D counterpart by measuring geometry of rigid features on the face. This avoids such pitfalls of 2D face recognition algorithms as change in lighting, different facial expressions, make-up and head orientation.

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