Building a Grasping Testbed
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Object Modelling:
1. Get pointclouds of given object from different perspectives using both IIWAS
2. Merge all pointclouds into one frame and create object Mesh

Grasp Simulation:
1. Send Mesh to V-REP simulator using API
2. Write a function cost = evaluate_grasp(Mesh, JointConfiguration)

Grasp Sampling:
1. Sample configurations according to $p(\theta | \text{Mesh}) \propto \exp \left( -\frac{1}{\beta} \text{cost}_{\text{Mesh}}(\theta) \right)$