Deep Learning for Robotic Grasp Detection

Project overview

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Version 1.0 (Draft)

2021

# Project Description

This project aims to look at the challenging

# Proposed Tasks

# Project Deliverables

The following are the expected project deliverables.

* **Model Dataset** – A dataset of depth images of models in varying positions, annotated with the best grasp pose for the object. This dataset will be used to train the DCNN model. This dataset may not
* **Neural Network Model** – A trained DCNN model (on the above dataset) that will be able to predict a grasp pose based on an input depth camera image of the object to be grasped.
* **Simulation Software** – A simulation of a robot that will apply the trained neural network model to detect grasp poses of unseen objects. This simulation will be used to evaluate the performance of the model.
* **Documentation** – This document will describe how to interface with the dataset and the neural network. This will be included as part of the appendix in the final report.

# Annotated Bibliography