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## **Technical Challenge - Hand/Gripper MVP Skill (Option 1)**

PyBullet + Franka Panda (parallel gripper) | Stable grasp with failure detection + mitigation

### **1. Summary**

I implemented a minimal manipulation skill that grasps a single object (a cube on a table) using the Franka Panda two-finger parallel gripper in PyBullet. Finite state machine (FSM) is used as the main logic with clear motion primitives (IK-based approach/descend/lift and open/close). One failure mode (bad grasp due to pose error) is detected and mitigated via a recovery routine that retries with adapted parameters.

### **2. Tools, Technologies and Gripper Model**

- Simulator: PyBullet (OS: Ubuntu 22.04, Python 3.10)
- Robot model: Franka Panda arm + two-finger gripper (URDF from pybullet\_data)
- Scene: plane + table + cube\_small (pybullet\_data assets)
- Control: PyBullet inverse kinematics + joint position control

### **3. Sensing Assumptions and Interaction Logic**

Sensing assumption: The object pose is taken from the simulator (ground truth). In a real system, this would be provided by a perception module (e.g., RGB-D pose estimate) and would include noise.

Policy: The behavior is implemented via FSM and is deterministic.

### **4. Code Structure**

src/env.py – simulation setup, world (table/cube), Panda loading, joint/link indexing

src/kinematics.py – grasp target generation and EE orientation helpers

src/motion.py – motion primitives (step\_sim, IK move\_ee\_pose, open/close gripper)

src/policy.py – FSM policy (states, transitions, grasp verification, recovery adaptation)

src/main.py – CLI entry point, wiring, demo mode selection

### **5. How to Run**

1) Clone the code from github at a suitable location:

```
git clone https://github.com/PAyush15/gripping-challenge-neura.git
```

2) Navigate to the root directory and create and activate a virtual environment:

```
python3 -m venv pybullet_sim_env && source venv/bin/activate
```

2) Install dependencies:

```
pip install -r requirements.txt
```

3) Run (success demo):

```
python -m src.main
```

4) Run (recovery demo):

```
python -m src.main --recovery-demo
```

## 6. Interaction Logic (FSM)

States: RESET → APPROACH → DESCEND → CLOSE → VERIFY\_GRASP → LIFT → HOLD → SUCCESS, with RECOVER as the failure branch and FAIL after 3 retries.

- APPROACH: move end-effector to a safe pregrasp pose above the object.
- DESCEND: move to grasp pose computed from object pose + z\_offset.
- CLOSE: close both finger joints.
- VERIFY\_GRASP: check contact points between robot and object (min\_contacts threshold).
- LIFT/HOLD: lift to a fixed height and hold for a short duration.

## 7. Failure Mode and Mitigation (Recovery Demo)

Failure detected: Unsuccessful grasp (insufficient contacts after closing), which corresponds to a bad approach pose or insufficient grasp depth.

Mitigation: Bounded recovery with retry and parameter adaptation.

Recovery behavior:

- 1) Open gripper and move to a safe pose above the object.
- 2) Recompute grasp targets from the current object pose (simulates calculating the object pose again from sensor reading in real systems).
- 3) Adapt grasp depth: Grasp\_Z is reduced by a fixed step per retry until it reaches a min value (to avoid collision with table).
- 4) Retry from APPROACH (max\_retries bounded).

Recovery demo scenario:

- Attempt 1: inject a small XY pose error (models perception/calibration error) so the fingers miss the cube.
- Attempt 2: XY error corrected, but grasp\_z is intentionally kept above the object, causing it to fail due to insufficient grasp.
- Attempt 3: RECOVER reduces grasp\_z, enabling stable grasp and successful lift.

## 8. Use of AI Tools During Development

AI tools were used for following tasks: clarifying PyBullet API usage, suggesting modular file organization, implementing argument parse to better run the demo (--recovery-demo) and documentation. All manipulation/control decisions (state definitions, transitions, failures, recovery strategy, and parameter tuning) were implemented by me.