

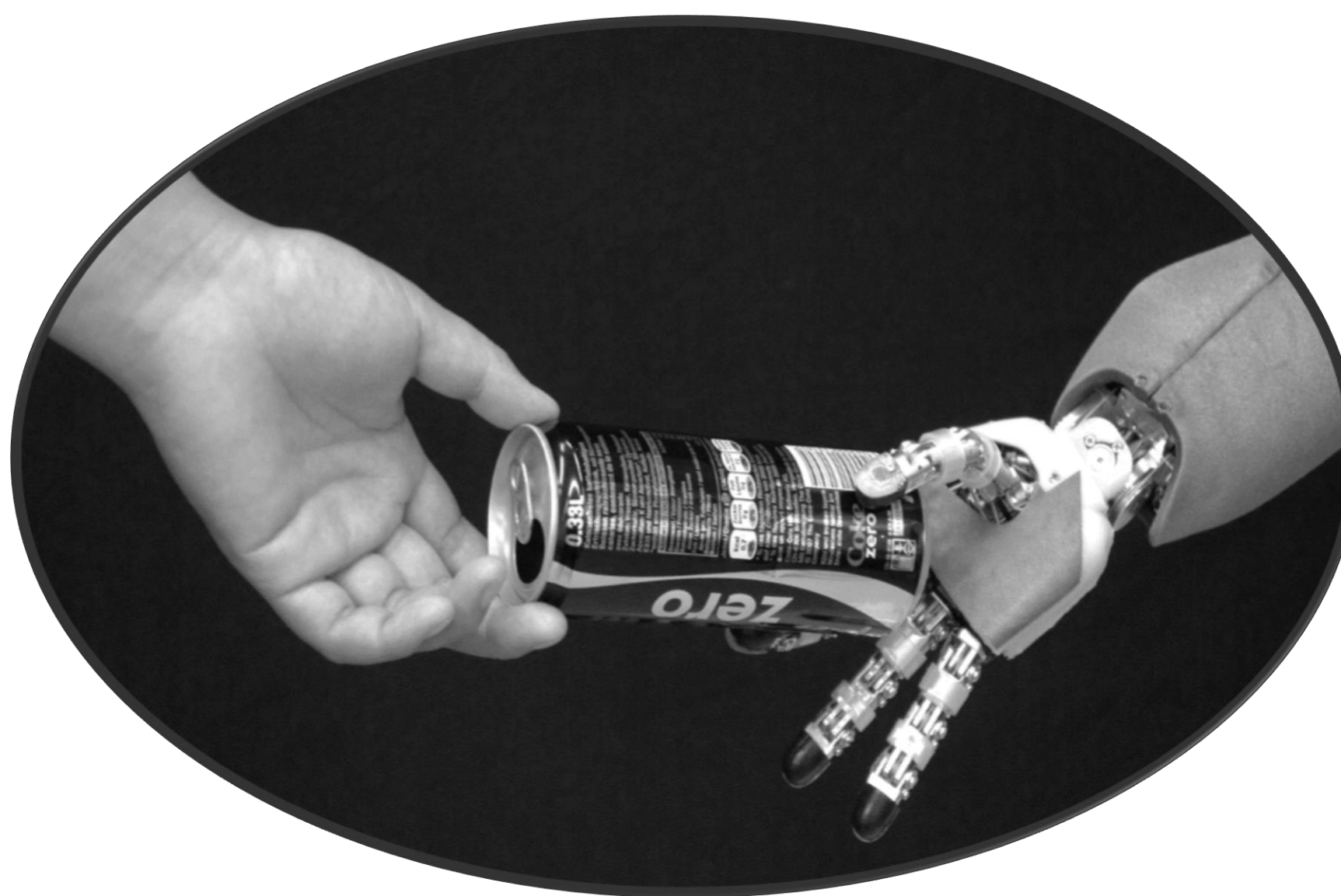
# CORSMAL

## Collaborative Object Recognition, Shared Manipulation And Learning

### Scope

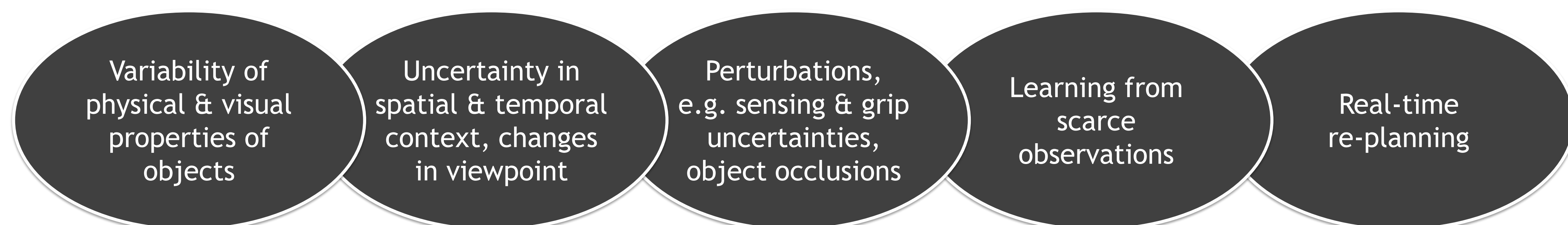
Exploring the fusion of **multiple sensing modalities** (touch, sound, and vision) to accurately and robustly estimate the **physical properties** of objects in noisy and potentially ambiguous environments

Designing a framework and creating a dataset for **recognition** and **manipulation** of objects



### Objectives & Challenges

- to **infer** object **content** by observing the way the human manipulates it
- to decide the parameters for **grasping** (grasping points, stiffness) based on inference of the content
- to **adapt grip** if the object slips



### Partners



### Team



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### Sponsors



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<http://corsmal.eecs.qmul.ac.uk>

