
Coupling between Perception and Manipulation: Learning to Grasp Objects in Highly Cluttered Environments

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<https://rugcognitiverobotics.github.io>

Assignment Overview

Service robots typically use a perception system to perceive the world. In particular, perception systems provide valuable information that the robot has to consider for interacting with users and environments. To assist humans in various daily tasks, a robot needs to know *how to grasp and manipulate objects in different situations*. For instance, consider a clear table task, where a robot needs to remove all objects from a table and put them into a basket. Such tasks consist of two phases: the first phase is dedicated to the perception of the object, and the second phase is about the planning and execution of the manipulation task. In this assignment, we mainly focus on deep visual object grasping and manipulation.

The main goal of this assignment is to make a coupling between perception and manipulation using eye-to-hand camera coordination. Towards this goal, we have developed a simulation environment in [PyBullet](#), where a Universal Robot (UR5e) with a two-fingered Robotiq 2F-140 gripper perceives the environment through an RGB-D camera. The experimental setup for this assignment is shown in Fig. 1. This setup is very useful to extensively evaluate different object grasping approaches. After successful completion of this assignment, students will be able to implement and experiment several methods for object grasping.

Traditional object grasping approaches explicitly model how to grasp different objects by considering prior knowledge about object shape, and pose. It has been proven that it is hard to obtain such prior information for never-seen-before objects in human-centric environments. More recent approaches try to tackle this limitation by formulating object grasping as an *object-agnostic* problem, in which grasp synthesis is detected based on learned visual features without considering prior object-specific information. In this vein, much attention has been given to object grasping approaches based on Convolutional Neural Network (CNN). Among deep visual grasping approaches, GR-ConvNet [1] showed the state-of-the-art results. In particular, GR-ConvNet receives an RGB and a Depth images and generate a pixel-wise grasp configuration. As an example of how to use CNN in visual grasping experiments, we have integrated the GR-ConvNet to our setup.

In this assignment, we are pursuing three main goals: (i) learning about **at least two** deep visual grasping approaches, (ii) evaluating and comparing their performances in three scenarios including, *isolated*, *packed*, and *pile* scenarios (see Fig. 2); (iii) investigating the usefulness of formulating object grasping as an object-agnostic problem for general purpose tasks. You can also use this setup to develop your **final course project**.

In this assignment, we use simulated YCB objects dataset [2]. All objects were inspected to be sure that at least one side of the object fits within the gripper.

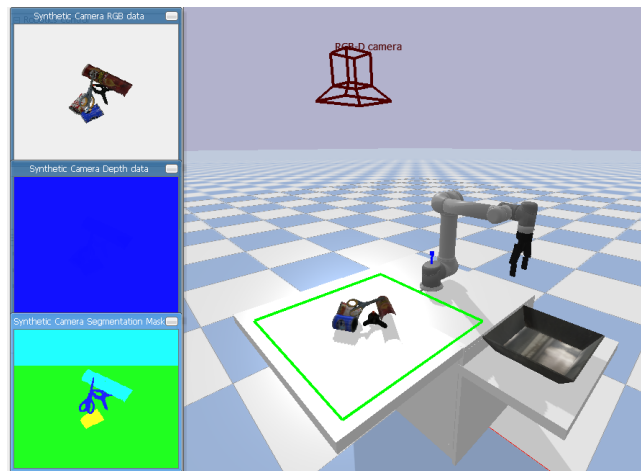


Figure 1: Our experimental setup consists of a table, a basket, a UR5e robotic arm, and objects from the YCB dataset. The green rectangle shows the robot's workspace, and the camera indicates the pose of the camera in the environment. Synthesis RGB and depth images, together with a segmentation mask are shown on the left side of the figure.



Figure 2: Illustrative examples of three evaluation scenarios: (left) isolated; (center) packed and (right) pile of objects.

Your tasks

This assignment comprises two parts, each worth 50% of your grade. **For the first part**, you need to understand and describe how this system works by reading GR-ConvNet paper, checking the provided code, and examining its performance in *isolated*, *packed*, and *pile* scenarios. We explain the evaluation scenarios and metrics below.

For the second part of this assignment, you need to select another deep visual grasping approach and integrate it into the system. Similar to the previous part, you need to evaluate the model in isolated, packed, and pile scenarios. Finally, you need to analyze and compare the obtained results with the GR-ConvNet model.

It should be noted that it is possible to select a 3D based deep learning approach (e.g., [3, 4, 5, 6]), or depth only based approaches (e.g., [7]), or even data-driven approach (e.g., [8]) instead of RGB-D image based approach. To convert the RGB-D image to point cloud you can use [Open3D](#) library. In the case of deep learning approaches, we strongly recommend using pre-trained models.

To evaluate a grasping approach, you need to performed 10 rounds of experiments per scenario and analysis the obtained results. In each pile and packed experiment, we randomly generate a new scene consisting of five objects, while for the isolated object scenario, we place a randomly selected object in an arbitrary pose inside the robot's workspace. In all experiments, the robot knows in advance about the pose of the basket object as the placing area, while the robot needs to predict grasp synthesis for the given scene and select the best graspable pose to grasp an object, pick it up, and put it in the basket. Note that, at the beginning of each experiment, we set the robot to a predefined setting, and randomly place objects on the table.

A particular grasp is recorded as a success if the object is inside the basket at the end of the experiment. You need to report the performance of an approach by measuring $\text{success_rate} = \frac{\text{number of successful grasps}}{\text{number of attempts}}$.

In the case of pile and packed scenarios, to generate a simulated scene containing a pile of objects, we randomly spawn objects into a box placed on top of the table. We wait for a couple of seconds until all objects become stable, and then remove the box, resulting in a cluttered pile of objects. To generate a packed scenario, we iteratively placed a set of objects next together in the workspace. These procedures are shown in Fig. 3.

For the pile and packed scenarios, in addition to the `success_rate`, you need to report the average percentage of objects removed from the workspace. An experiment is continued until either all objects get removed from the workspace, or three failures occurred consecutively. Note that, the system automatically reports a summary of the obtained results in the “results” folder.

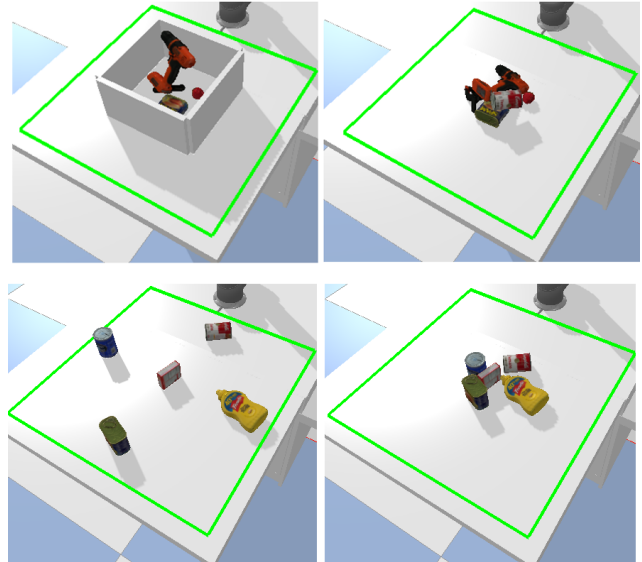


Figure 3: Generating random scenes to make: (*top-row*) pile of objects; or (*bottom-row*) packed objects.

What we offer for this assignment

- A detail instruction about how to install and run the experiments. Check the [GitHub repository](#)
- Automatically report the obtained results after each round of experiments.

Policies

- Feel free to collaborate on solving the problem but please write your code individually. **In particular, do not copy code from other students.**
- **You are not allowed** to use this code in other projects (even if the code is partially used). If you want to publish your results as a scientific paper or use this framework in other projects, contact [Hamidreza Kasaei](#) (hamidreza.kasaei@rug.nl) directly and discuss the case explicitly.

Submission

At the end of each practical assignment, a report (i.e., up to three pages [IEEE conference format](#)) has to be delivered. At the end of the report, you have to include an “Authors’ Contributions” section, and explain how did you divide the

work among the members, and what are the contributions of each author. We expect all authors contribute equally to the assignment. This assignment prepares students to do the final course project. Submit your assignment in as a pdf file named `group_number_prj2.pdf`

References

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