											В	-DACI	/I-S-0.1	scorin	g shee	t					
	-																				
	Table dir Length	nensions 120		Length	cloth dime	ensions 240															
	Width	70		Width		145															
														Indicate plann	ed grasping poin	its					
					h ₅																
				h ₆	h ₂	h ₃	h,	h ₁	h ₂												
				_	_		_		\rightarrow				-								
Starting	Success [MAN] Success [GR2 (1 0) (1 0)		R2] Success [GR1] (1 0)	1						Quality function	Quality function in	Quality function in	Time	For	e measures (no	rm in N)	1	Used		Used	
config.	(1 0)	(1 0)	(1 0)	h1	h2	h3	h4	h5	h6	rotation	length	width	in sec	min	avg	max	Assumptions	(YES NO)	Assumptions	(YES NO)	New assumptions
				_	-	-			-	0	0	0					Table color				
r01				_	+	_				0	0	0	-	_			Table position				
[pg2]				_	+		-			0	0	0					Illumination changes				
-				_	+	_	-	-	 	0	0	0	+	+	+	1	Tablecloth color Tablecloth dimensions				
				-	1	-	_	-		U	U	U U					rapidototi diliferisions	l .			
													avg: -	avg: -	avg: -	avg: -					
ummary:	0.00%												var: -	var: -	var: -	var: -	Assumptions:	0/5	New assumptions:	:	NO
starting	Success	Success [GR2]	Success (CD4)							Quality function	Quality function in	Quality function in	Time	For	e measures (no	rm in N)		Used		Used	
config.	[MAN] (1 0)	(1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	rotation	length	width	in sec	min	avg	max	Assumptions	(YES NO)	Assumptions	(YES NO)	New assumptions
																			Folded to make robot grasp short		
-										0	0	0					Table color		edge of tablecloth		
[pg1]										0	0	0					Table position		Illumination changes		
11-9-1										0	0	0	1	-			Object position				
-				-	+	-				0	0	0	-				Tablecloth color Tablecloth dimensions				
				_	_					0	0	0					rablecioth dimensions				
ummary:	0.00%	0.00%											avg: -	avg: -	avg: -	avg: -	Assumptions:	0/7	New assumptions:		NO
										-	-	-	var: -	var: -	var: -	var: -					
	Success									Quality	Quality	Quality		For	ce measures (no	rm in N\					
Starting	[MAN]	Success [GR2]	Success [GR1]	١	1	l				function	Quality function in	function in	Time				 	Used		Used	
config.	(1 0)	(1 0)	(1 0)	h1	h2	h3	h4	h5	h6	rotation	length	width	in sec	min	avg	max	Assumptions	(YES NO)	Assumptions	(YES NO)	New assumptions
				_	+				-	0	0	0	-	_			Table color		Grasp points visible on table		
										0	0	0					Table position		Illumination changes		
[cr]										0	0	0					Object position		Cloth placed to make robot grasp the short edge of tablecloth		
1					1					0	0	0	1				Tablecloth color				
										0	0	0					Tablecloth dimensions				
Summary:	0.00%	avg: - avg: -							avg: -	avg: -	avg: -	Assumptions:	0/8	New assumptions:		NO					
illillary.	0.00 /6	0.00 /6	0.00 /6								-	-	var: -	var: -	var: -	var: -	Assumptions.	0/8	New assumptions.		NO
	Cuor				_					Quality	011-114-1	0!!4-:		E	e measures (no	rm in N)					
Starting	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1]	I						function	Quality function in	Quality function in	Time		,		+	Used (YES NO)		Used (YES NO)	
config.	(1 0)	(1 0)	(1 0)	h1	h2	h3	h4	h5	h6	rotation	length	width	in sec	min	avg	max	Assumptions	(YES NO)	Assumptions	(YES NO)	New assumptions
										0	0	0					Table color		Top layer of folded tablecloth		
+				+	+	+	†	1	 	0	0	0	+	+	+		Table position		contains grasp point Illumination changes		
[fd]				1	1	t	t			· ·	1 0	— "	+	+	+				Folded to make robot grasp short		
,								<u></u>		0	0	0					Object position		edge of tablecloth		
Ī										0	0	0					Tablecloth color				
										0	0	0					Tablecloth dimensions				
ımmarv:	0.00%	0.00%	0.00%										avg: -	avg: -	avg: -	avg: -	Assumptions:	0/8	New assumptions:		NO
Summary:			0.00 /0					var: -	var: -	var: -	var: -										

Starting config.	[MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)					function rotation	function in length	function in width	Time in sec	min	avg	max	Assumptions:	New assumptions:	
[pg2]	0.00%							_	_	_	avg: -	avg: -	avg: - var: -	avg: -	0/5	NO	
[pg1]											avg: -	avg: -	avg: -	avg: -			
158.1	0.00%	0.00%						-	-	-	var: -	var: -	var: -	var: -	0/7	NO	
[cr]	0.00%	0.00%	0.00%						_	_	avg: - var: -	avg: -	avg: - var: -	avg: - var: -	0/8	NO	
[fd]											avg: -	avg: -	avg: -	avg: -			
į <u>1</u>	0.00%	0.00%	0.00%					-	-	-	var: -	var: -	var: -	var: -	0/8	NO	
Comments	Comments																
What makes the system successful?																	
What makes the system fail?																	
What was improved compared to other methods?																	
Chosen grasping points and/or grasping strategy.																	