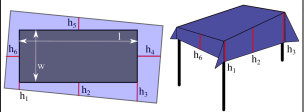


B-DACM-S-0.1 scoring sheet

Table dimensions		Tablecloth dimensions												Indicate planned grasping points								
Length	120	Length	240																			
Width	70	Width	145																			
Starting config.	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	Quality function rotation	Quality function in length	Quality function in width	Time in sec	Force measures (norm in N)			Assumptions	Used (YES NO)	Assumptions	Used (YES NO)	New assumptions	
[pg2]										0	0	0		min	avg	max	Table color					
										0	0	0					Table position					
										0	0	0					Illumination changes					
										0	0	0					Tablecloth color					
										0	0	0					Tablecloth dimensions					
Summary:	0.00%									-	-	-	avg: - var: -	avg: - var: -	avg: - var: -	avg: - var: -	Assumptions:	0/5	New assumptions:	NO		
Starting config.	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	Quality function rotation	Quality function in length	Quality function in width	Time in sec	Force measures (norm in N)			Assumptions	Used (YES NO)	Assumptions	Used (YES NO)	New assumptions	
[pg1]										0	0	0		min	avg	max	Table color		Folded to make robot grasp short edge of tablecloth			
										0	0	0					Table position		Illumination changes			
										0	0	0					Object position					
										0	0	0					Tablecloth color					
										0	0	0					Tablecloth dimensions					
Summary:	0.00%	0.00%								-	-	-	avg: - var: -	avg: - var: -	avg: - var: -	avg: - var: -	Assumptions:	0/7	New assumptions:	NO		
Starting config.	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	Quality function rotation	Quality function in length	Quality function in width	Time in sec	Force measures (norm in N)			Assumptions	Used (YES NO)	Assumptions	Used (YES NO)	New assumptions	
[cr]										0	0	0		min	avg	max	Table color		Grasp points visible on table			
										0	0	0					Table position		Illumination changes			
										0	0	0					Object position		Cloth placed to make robot grasp the short edge of tablecloth			
										0	0	0					Tablecloth color					
										0	0	0					Tablecloth dimensions					
Summary:	0.00%	0.00%	0.00%							-	-	-	avg: - var: -	avg: - var: -	avg: - var: -	avg: - var: -	Assumptions:	0/8	New assumptions:	NO		
Starting config.	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	Quality function rotation	Quality function in length	Quality function in width	Time in sec	Force measures (norm in N)			Assumptions	Used (YES NO)	Assumptions	Used (YES NO)	New assumptions	
[fd]										0	0	0		min	avg	max	Table color		Top layer of folded tablecloth contains grasp point			
										0	0	0					Table position		Illumination changes			
										0	0	0					Object position		Folded to make robot grasp short edge of tablecloth			
										0	0	0					Tablecloth color					
										0	0	0					Tablecloth dimensions					
Summary:	0.00%	0.00%	0.00%							-	-	-	avg: - var: -	avg: - var: -	avg: - var: -	avg: - var: -	Assumptions:	0/8	New assumptions:	NO		
Starting config.	Success [MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)	h1	h2	h3	h4	h5	h6	Quality function rotation	Quality function in length	Quality function in width	Time in sec	Force measures (norm in N)			Assumptions	Used (YES NO)	Assumptions	Used (YES NO)	New assumptions	
														min	avg	max						

Starting config.	[MAN] (1 0)	Success [GR2] (1 0)	Success [GR1] (1 0)					function rotation	function in length	function in width	Time in sec	<i>min</i>	<i>avg</i>	<i>max</i>	Assumptions:	New assumptions:
[pg2]	0.00%							-	-	-	avg: - var: -	avg: - var: -	avg: - var: -		0/5	NO
[pg1]	0.00%	0.00%						-	-	-	avg: - var: -	avg: - var: -	avg: - var: -		0/7	NO
[cr]	0.00%	0.00%	0.00%					-	-	-	avg: - var: -	avg: - var: -	avg: - var: -		0/8	NO
[fd]	0.00%	0.00%	0.00%					-	-	-	avg: - var: -	avg: - var: -	avg: - var: -		0/8	NO
Comments																
<ul style="list-style-type: none">What makes the system successful?What makes the system fail?What was improved compared to other methods?Chosen grasping points and/or grasping strategy.																