FBM 1: Object Perception

Team nar	ne:					
Referee I	:	, Referee II: _				
Date and	time:					
Notes:						
• Start	and end time are bas	ed on the referee stop w	vatch.			
• Time durat		the robot cannot detec	t the object within the specified test			
• GT is	s the ground truth wh	ich is the information p	rovided by the referee box.			
• Obje	ct identifier:					
_	AX-01(4)=bearing bo	M-02(2)=cover plate box type A, AX-16(3)=bex X-09(7)=motor, AX-03(earing box type B			
		End Time:, \Box	Timeout			
Object Det		n : D				
GT I	$\frac{\text{Container}}{\text{EM-01}(1) \mid \text{EM-02}(2)}$	Bearing Box AX-01(4) AX-16(3)	Transmission AX-02(6) AX-09(7) AX-03(5)			
Robot	Container EM-01(1) EM-02(2)	Bearing box AX-01(4) AX-16(3)	Transmission AX-02(6) AX-09(7) AX-03(5)			
Pose						
GT	х у θ	Robot	y θ			
Comments	:					
Run 2 Sta		End Time:, □	Timeout			
GT	Container	Bearing Box	Transmission			
Robot	EM-01(1) EM-02(2) Container	AX-01(4) AX-16(3) Bearing box AX-01(4) AX-16(2)	AX-02(6) AX-09(7) AX-03(5) Transmission AX-02(6) AX-02(7) AX-02(5)			
Pose	EM-01(1) EM-02(2)	AX-01(4) AX-16(3)	AX-02(6) AX-09(7) AX-03(5)			
GT	x y θ	Robot	y θ			
Comments	:					

	Start Time:	, E	and Time:	, \square	Timeout			
Object I	Detection							
GT		Eainer EM-02(2)	Bearing AX-01(4)	Box AX-16(3)	Transmission AX-02(6) AX-09(7) AX-03(5)			
D 1 /	` ′	tainer	Bearing	()	` ′	Transmission		
Robot	EM-01(1)	EM-02(2)	AX-01(4)	AX-16(3)	AX-02(6)	AX-09(7) AX-03(5)		
Pose								
GT	x y θ		Robot	X	У	θ		
Commen	ts:							
Run 4 S	Start Time:	, E	and Time:		Timeout			
Object I	Detection							
GT		Eainer EM-02(2)	Bearing AX-01(4)		AX-02(6)	$\begin{array}{ c c c c }\hline \text{Transmission} \\ \hline AX-09(7) & AX-03(5) \\ \hline \end{array}$		
Robot	Cont EM-01(1)	Eainer EM-02(2)	Bearing AX-01(4)	x box AX-16(3)	AX-02(6)	$\begin{array}{ c c c c }\hline \text{Transmission} \\ \hline & AX-09(7) & AX-03(5) \\ \hline \end{array}$		
Pose								
GT	X	y θ	Robot	X	У	θ		
Commen	ts:							
Run 5 S	Start Time:	, E	and Time:		Timeout			
Object I	Detection							
GT		ainer	Bearing	Box	Transmission			
GI	EM-01(1)	EM-02(2)	()	AX-16(3)	AX-02(6)	AX-09(7) AX-03(5)		
	Cont EM-01(1)	Eainer EM-02(2)	Bearing AX-01(4)	3 box AX-16(3)	AX-02(6)	$\frac{\text{Transmission}}{\mid AX-09(7) \mid AX-03(5)}$		
Robot		EM-02(2)	ΑΛ-01(4)	AA-10(3)	$A\Lambda$ -02(0)	AX-09(7) AX-03(5)		
	LIVI OI(I)							
Robot Pose			II .	П				
	X X	y θ	Robot	X	У	θ		
Pose	X	y θ	Robot	X	У	θ		

Run 6 S	Start	Time: $_{-}$		_, E	nd T	$Γime: _$			Timeou	ut				
Object I	Detect	tion												
CT	Container				Bearing Box			Transmission						
GT	EM	-01(1)	EM-02	(2)	AX-01(4) AX-16(3)			AX-02	2(6)	AX	-09(7) A	AX-03(5)	
Dahat	Container			Bearing box					Trans	missi	ion			
Robot	EM	-01(1)	EM-02	(2)	AX-01(4) AX-16(3)			AX-02	2(6)	AX	-09(7) A	AX-03(5)	
Pose														
GT	x y θ			Robot			y θ							
G1 					Robot									
Commer	nts:													
Run 7 S	Start	Time: _		_, E	nd T	Γ ime: $_$			Timeou	ut				
Object I	Detect	tion												
	Container			Bearing Box				Transmission						
GT	EM-01(1) EM-02(2)			(2)	AX-01(4) AX-16(3)			AX-02(6) AX-09(7) AX-03(5)						
Robot	Container			Bearing box					Trans	missi	ion			
10000	EM-01(1) EM-02(2)			AX-01(4) AX-16(3)			AX-02(6) AX-09(7) AX-03(5)							
Pose														
GT		X	у	θ		Robo	<u> </u>	X	у		θ			
G1						Robo	և							
Commer	nts:													
	105													
Run 8 S	Start	Time: _		_, E	nd T	$Γ$ ime: $_$			Timeou	ut				
Object I	Detect	tion												
	Container			Bearing Box			Transmission							
GT	EM	$EM-01(1) \mid EM-02(2)$			AX-01(4) AX-16(3)			AX-02(6) AX-09(7) AX-03(5)						
D 1 /	Container			Bearing box			Transmission							
Robot	EM-01(1) EM-02(2)			AX-01(4) AX-16(3)			AX-0	2(6)	AX	-09(7) A	AX-03(5)		
Pose														
- CIT		x	у	θ		D 1		X	у		θ			
GT						Robo	t							
	1									•				
Commer	10S:													

Run 9 S	Start Time: .	, E	and Time: _		Timeout			
Object I	Detection							
GT	Container EM-01(1) EM-02(2)			ng Box AX-16(3)	Transmission AX-02(6) AX-09(7) AX-03(5)			
Robot	Cont EM-01(1)		Bearin AX-01(4)	ng box AX-16(3)	AX-02(6)	Transmission AX-09(7)	AX-03(5)	
Pose								
GT	X	y θ	Robot	X	У	θ		
Commen	nts:							
	Start Time:	,	End Time:	, □	☐ Timeout			
Object 1		•	D :	D	I	<u></u>		
GT	Cont EM-01(1)		AX-01(4)	ng Box AX-16(3)		$\frac{\text{Transmission}}{ \text{AX-09}(7) }$	AX-03(5)	
Robot	\ /	Container Bearing box Transmission			` '			
Pose								
GT	X	y θ	Robot	X	У	θ		
Commen	nts:							
	narking dat eader signa				,			
Referen	signature:							
TOTELER	signature.							

FBM 2: Visual Servoing

Team name:	
Referee I:	, Referee II:
Date and time:	
Notes:	
• The start and the end time for each	n run are based on the referee stop watch.
• Timeout is checked when the robo duration.	ot cannot grasp the object within the specified test
• The sequence of objects which are u	used in each run is defined by the team.
v e /	EM-02=cardbox black, AX-01=bearing box type A, 2=bearing, AX-03=axis, AX-09=motor
	, \square Timeout Orientation:, \square Success, \square Dropped
Comments:	, \square Timeout Orientation:, \square Success, \square Dropped
Run 3 Start time:, End time: Object id:, Comments:	Orientation:, \Box Success, \Box Dropped
Run 4 Start time:, End time: Object id:, Comments:	Orientation:, $\ \square$ Success, \square Dropped
Run 5 Start time:, End time: Object id:, Comments:,	Orientation:, \Box Success, \Box Dropped

Run 6 Start time:, End	time:, \Box Timeout	
Object id:	, Orientation:,	\square Success, \square Dropped
Comments:		
Run 7 Start time:, End	time:, \Box Timeout	
Object id:	, Orientation:,	\square Success, \square Dropped
Comments:		
Benchmarking data delivered	appropriately: \square yes $/$ \square no	
Team leader signature:		
Referee signature:		