# Deep Learning for Tactile Perception

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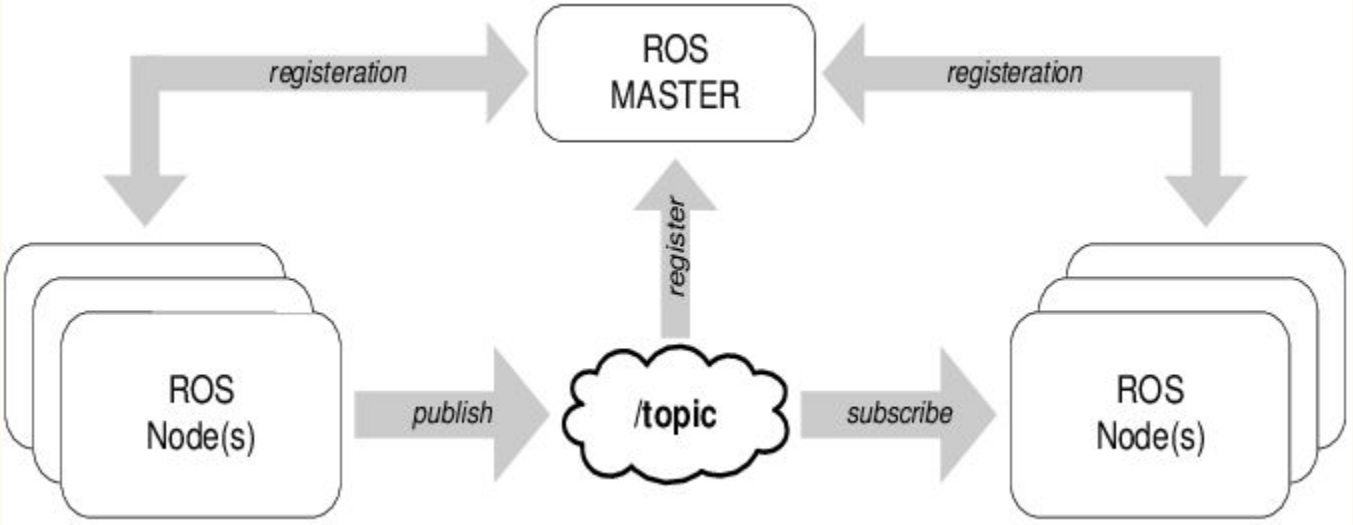
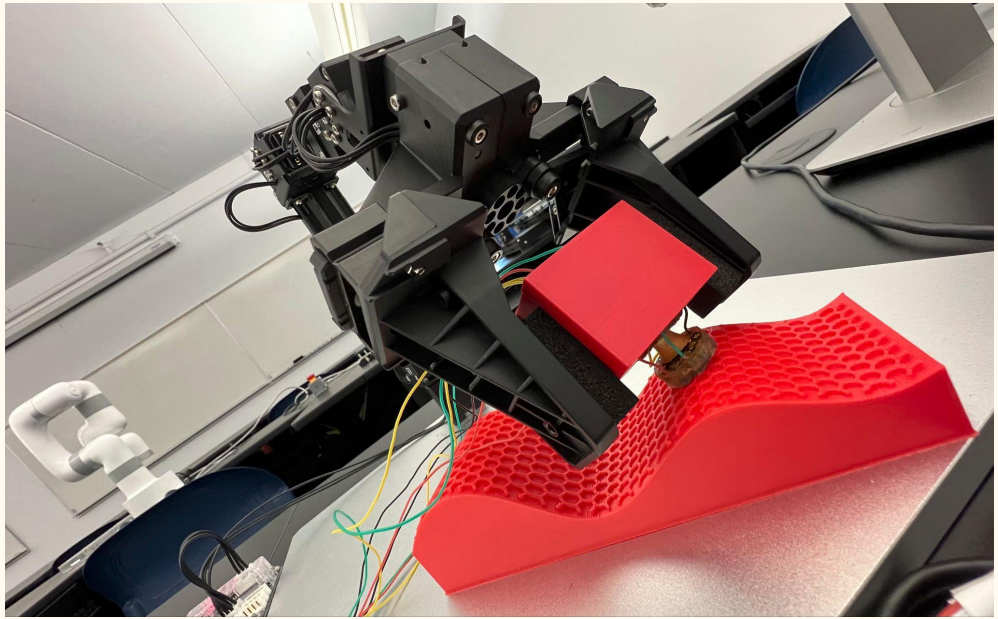
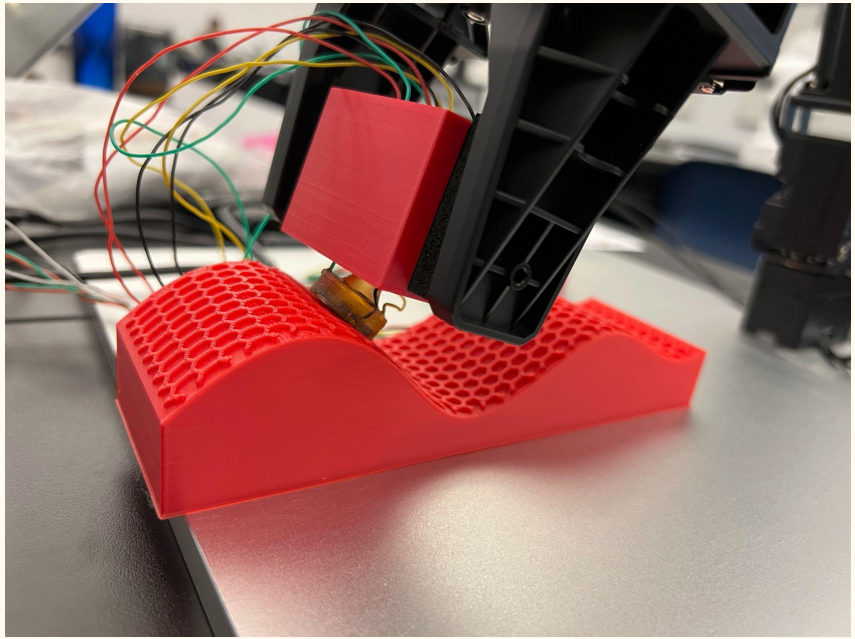
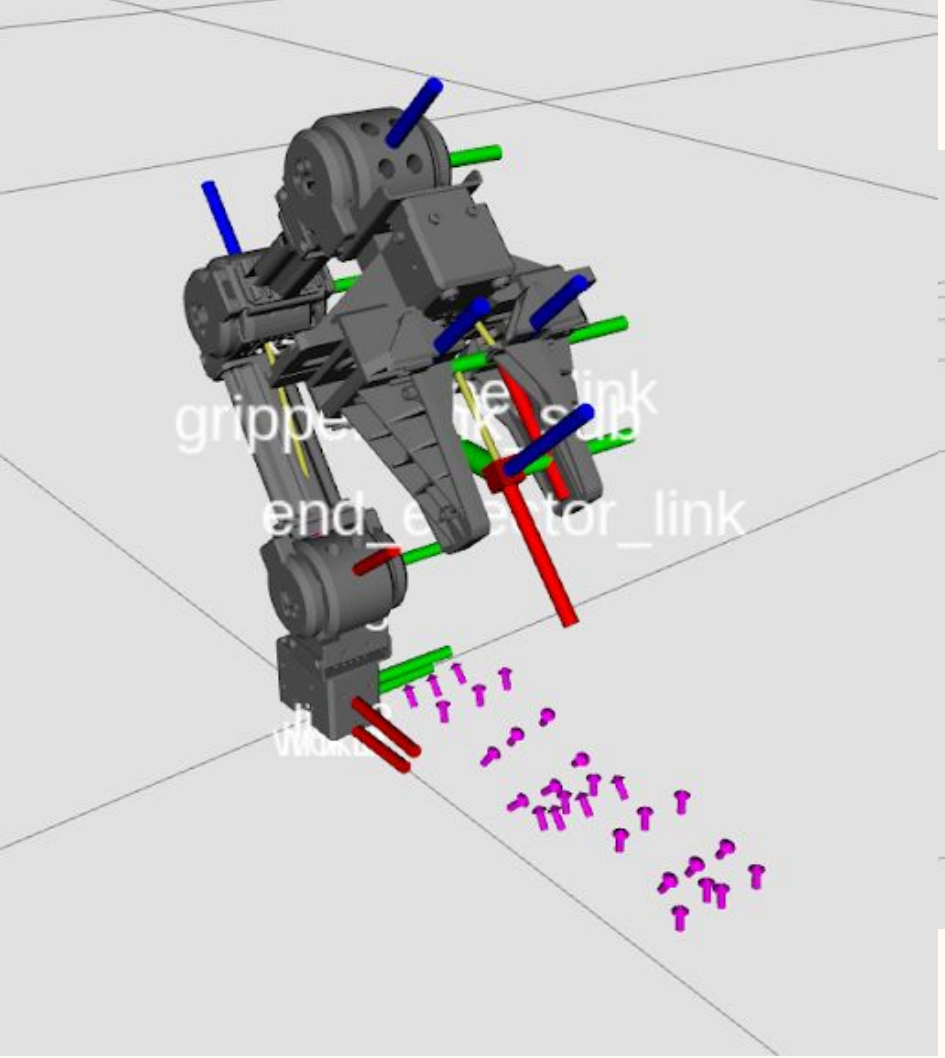
# ROS

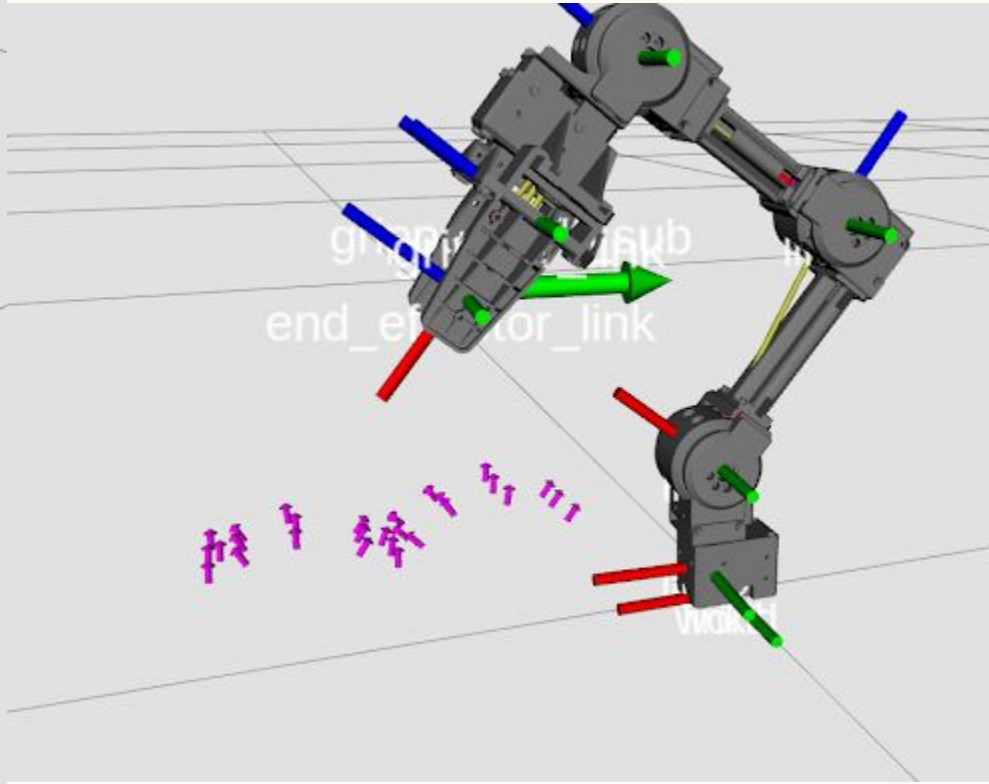

registeration
ROS
MASTER
registeration
register
ROS
Node(s)
publish
/topic
subscribe
ROS
Node(s)

# Collecting Points of the Object:

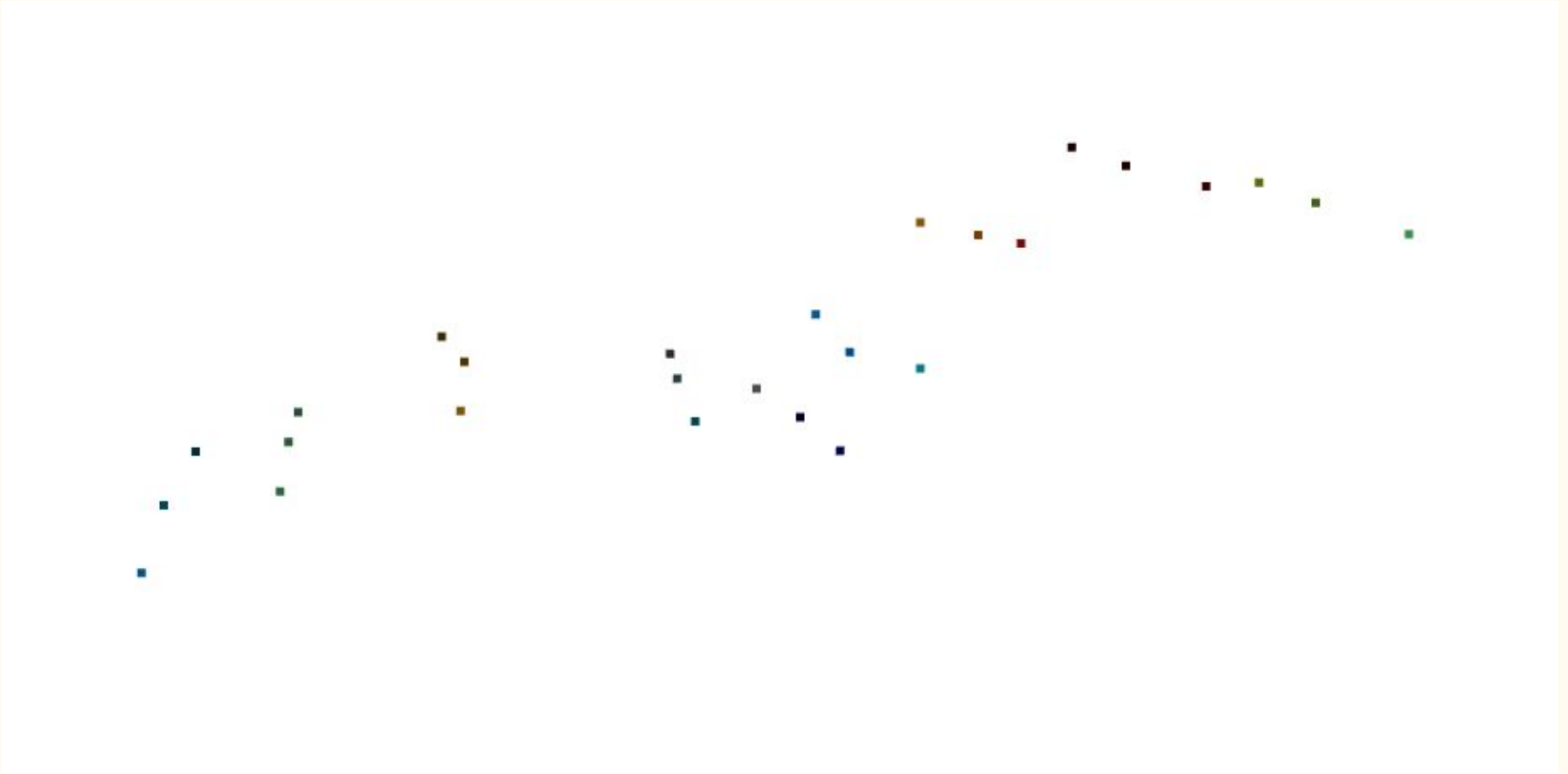


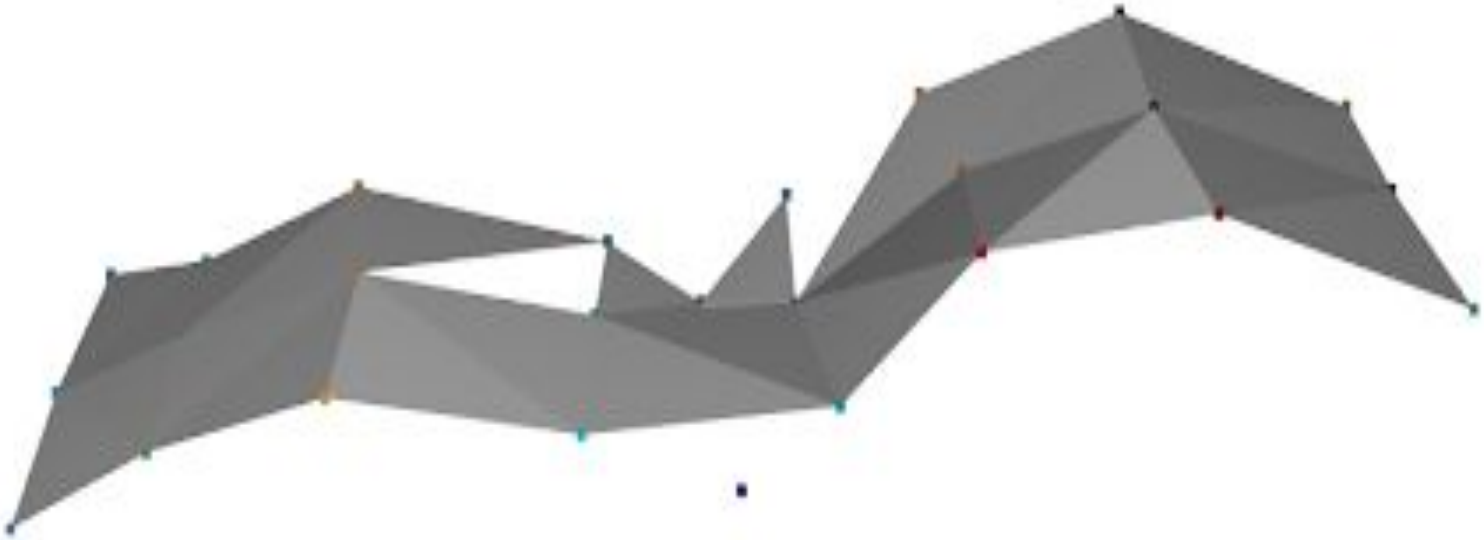



end_effector_link



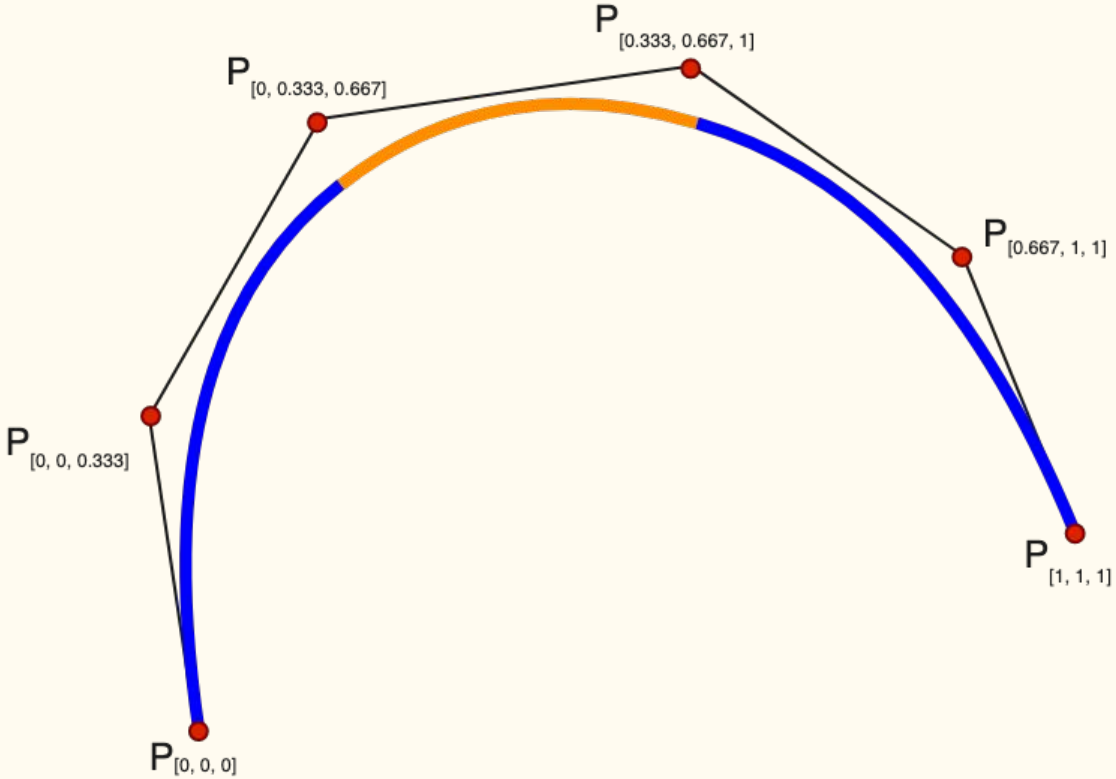
# Estimate the Shape of the Object:

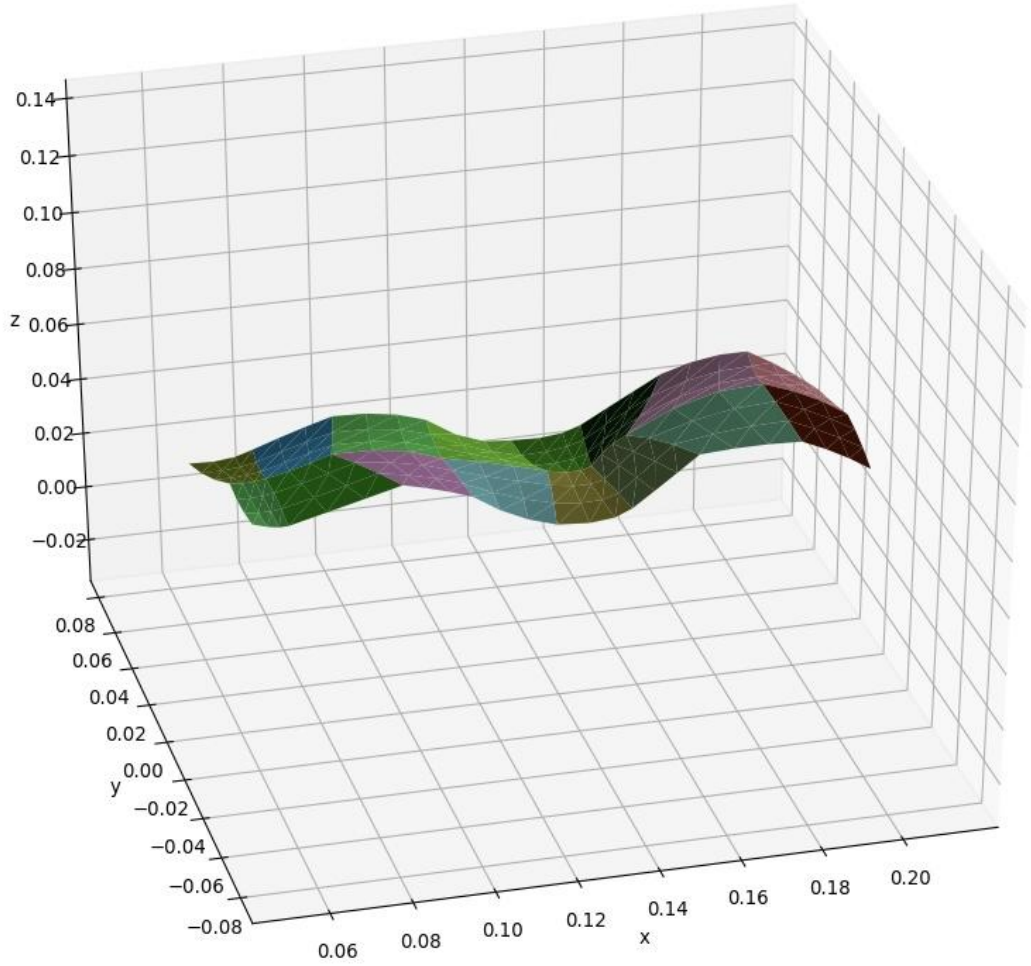




# Tactile Object Shape Perception

- Points Based

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0.08
z 0.06
0.04
0.02
0.00
−0.02
0.08
0.06
0.04
0.02
y 0.00
−0.02
−0.04
−0.06
−0.08
0.06
0.08
0.10
0.12
0.14
0.16
0.18
0.20
x

# Thank You