



THE UNIVERSITY OF
CHICAGO

Department of Statistics

MASTER'S THESIS PRESENTATION

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Grasping with Visual and Semantic Features

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Jones 304, 5747 S. Ellis Avenue

ABSTRACT

We propose using deep learning methods on a recent grasping database with added semantic features to predict stable grasp locations along an object surface. While previous work demonstrates that deep learning methods are effective tools for modeling grasp success, we determine if incorporating object characteristics allows for richer and more accurate models. Our research suggests cues from natural language instructions could potentially be used to improve robotic grasp success by helping to determine object features.

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