

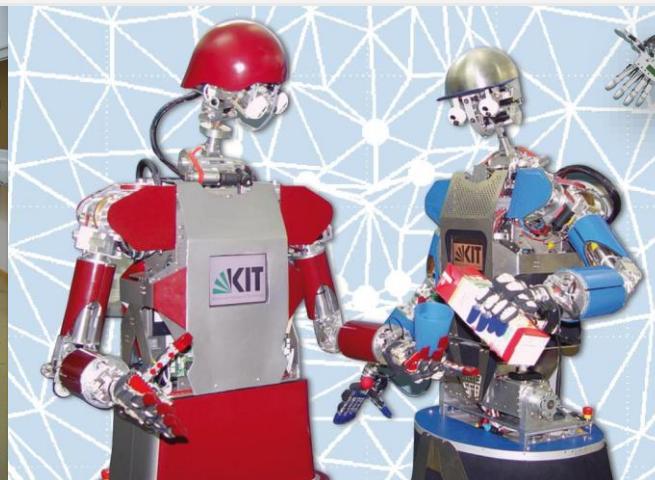
Humanoid Robotics @ KIT

Tamim Asfour

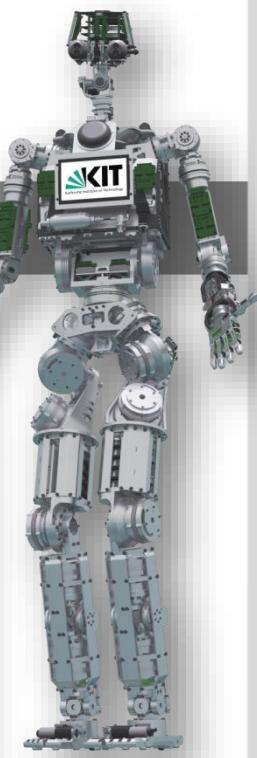
Institute for Anthropomatics and Robotics (IAR), High Performance Humanoid Technologies (H²T)



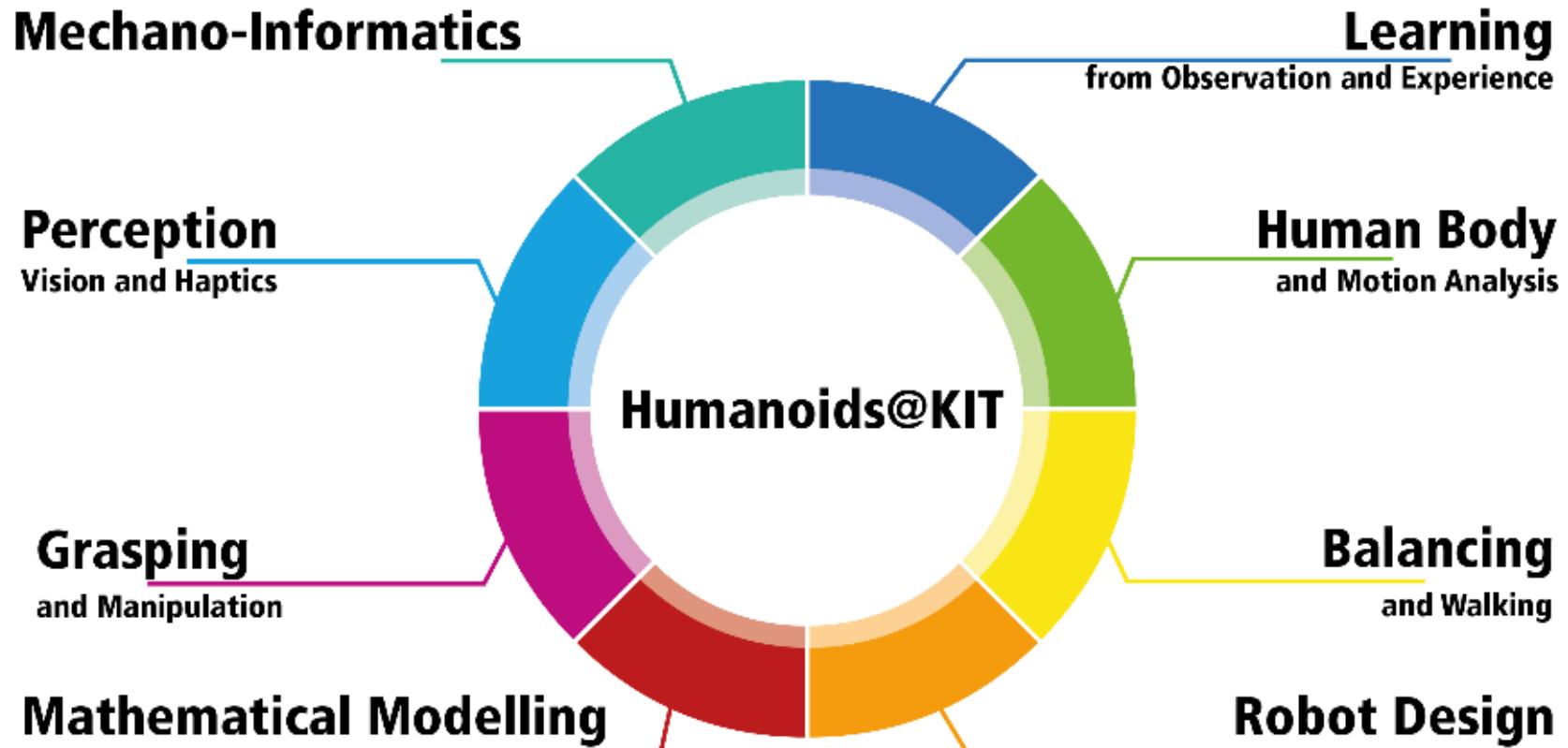
<http://www.humanoid.kit.edu>



<http://h2t.anthropomatik.kit.edu>



H²T Research Topics



Research Topics @ H²T

■ Grasping and manipulation

- Integration of vision and haptics to deal with unknown objects
- Active perception for object segmentation
- Vision-based localisation
- Mobile manipulation



■ Learning for human observation

- Marker-based (and markerless) observation of human actions
- Learning motion primitives from human demonstration
- Motion primitives for grasping, walking and whole-body locomotion and manipulation tasks

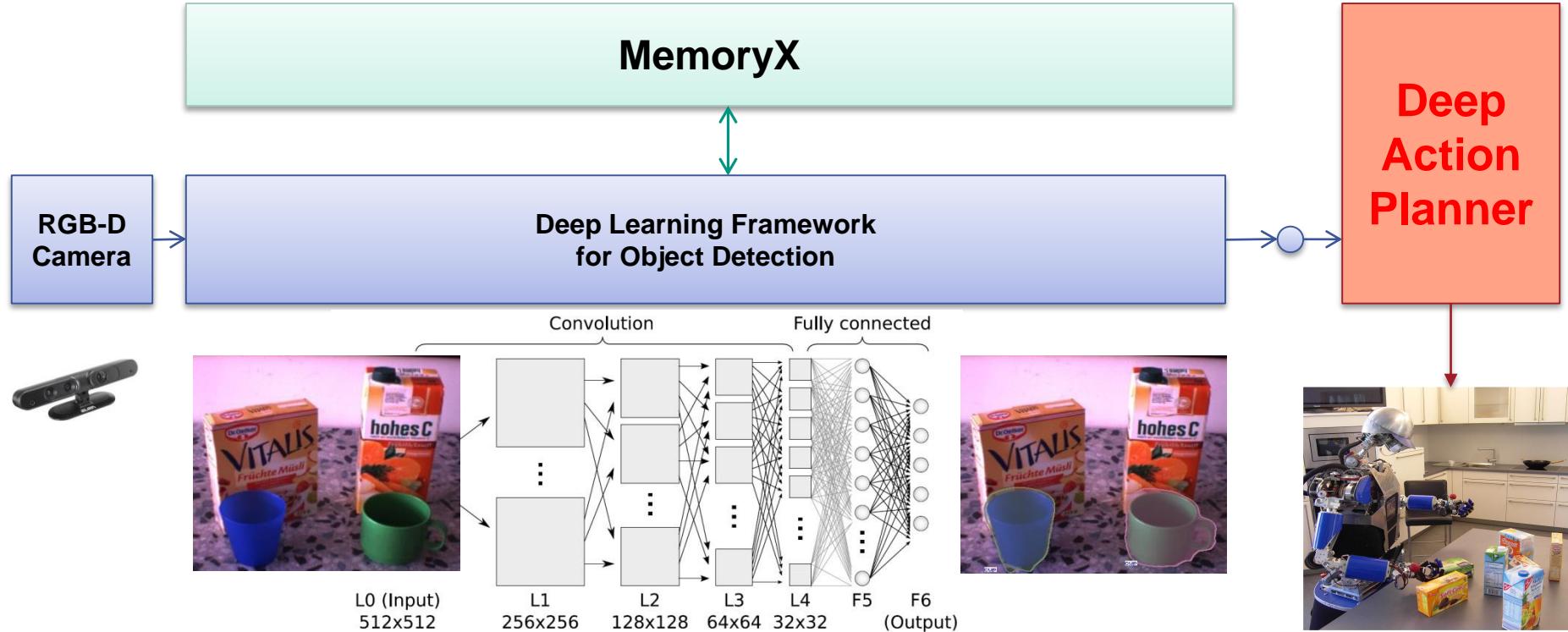


Praxis der Forschung in WS 16/17 am H²T

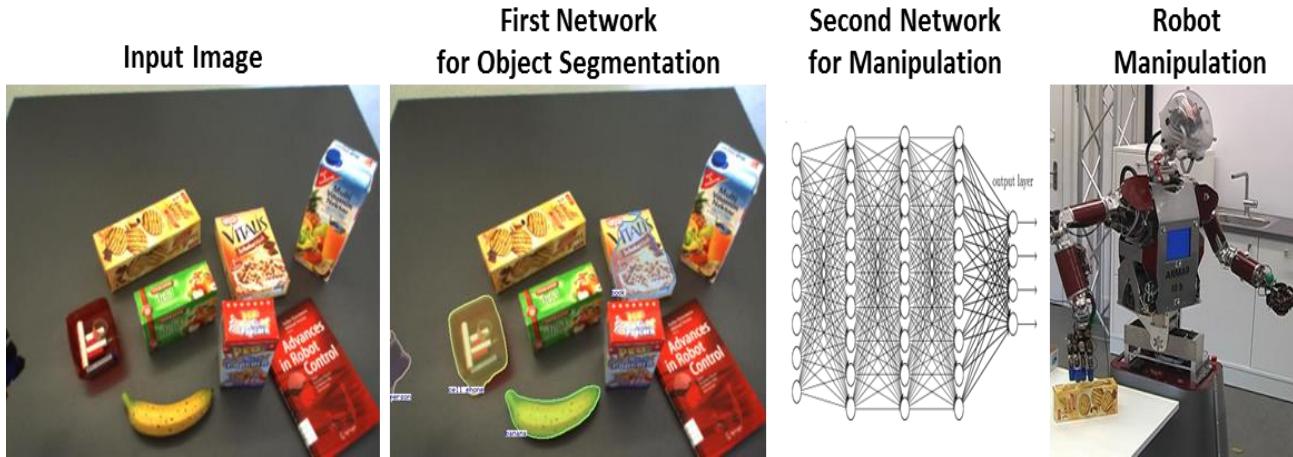
Two Topics

- 1. Deep Learning for Object Manipulation**
- 2. Reactive Grasping of Unknown Objects**

1. Deep Learning for Object Manipulation



1. Deep Learning for Object Manipulation



Goal

- Applying RNN-based deep learning techniques to allow ARMAR to explore the possible actions that objects suggest
- Collecting and annotating data for training the proposed deep architecture

Requirements

- Knowledge in computer Vision, robotics, and machine learning
- Solid programming skills in C/C++ (or Python)

2. Reactive Grasping of Unknown Objects

■ Task

- Design a closed-loop reactive grasping controller
- Data fusion of vision and haptics
- Online grasp execution

■ Methods

- Comparison of different data-driven methods (SVM, Gaussian Processes, ...)
- Data collection with ARMAR-III

■ Requirements

- Solid programming skills in C++
- Solid background in math



H²T „special“ requirements for PdF

- Candidates **must** spend at least one day per week in the H²T labs

Contact

- H²T, Geb. 50.20

www.humanoids.kit.edu



- Tamim Asfour
asfour@kit.edu



- Eren E. Aksoy
eren.aksoy@kit.edu



- You Zhou
you.zhou@kit.edu



- Simon Ottenhaus
simon.ottenhaus@kit.edu

