Grasp Recording
[GraspIt!]

Motion Planning
[OpenRAVE]

Motion Execution
[RT System]

B. Our Approach

A. Hardware Overview

$$T_I = \begin{bmatrix} 1 & 0 & 0 & -0.02 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$B = [\,O, O, O, O, O, O, O, O, O, O,$$

C. Motion Planning

D. Motion Execution

A. Experiment in Simulation