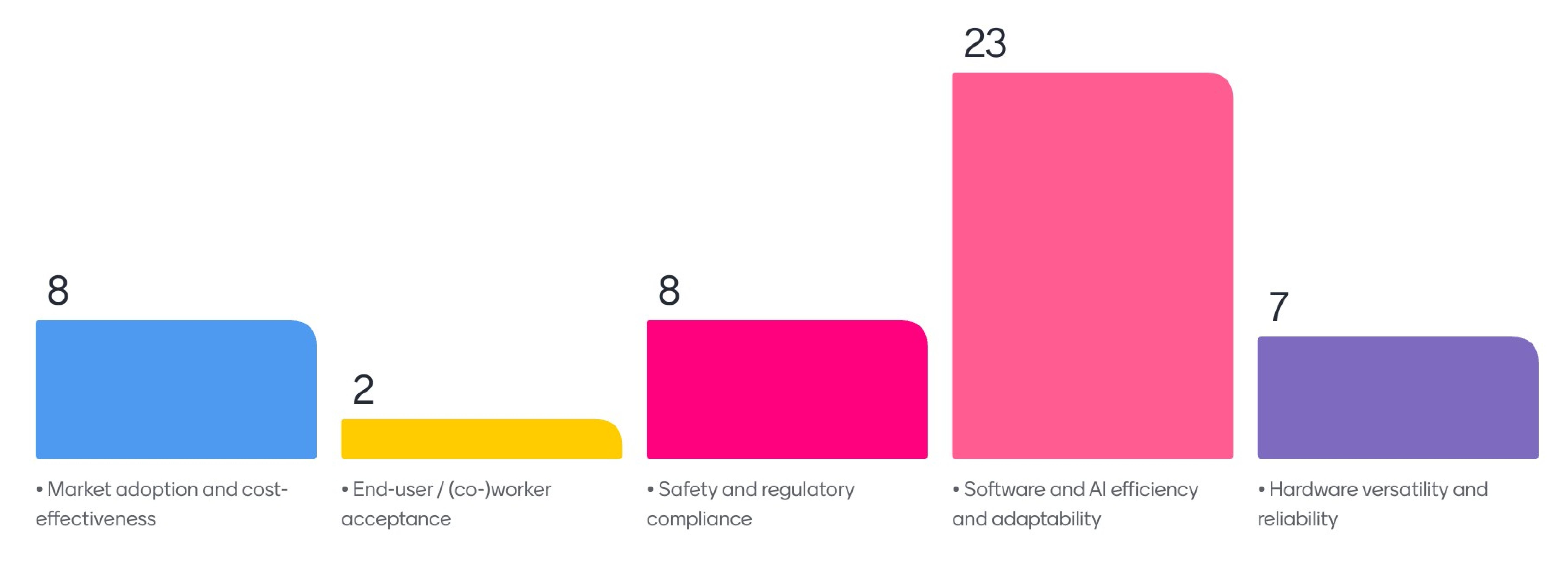
### Rapid Skill Learning with Hand-Held Grippers in IntelliMan

What do you see as the biggest challenge for enabling rapid skill learning in robotic manipulators designed to handle a wide variety of objects?

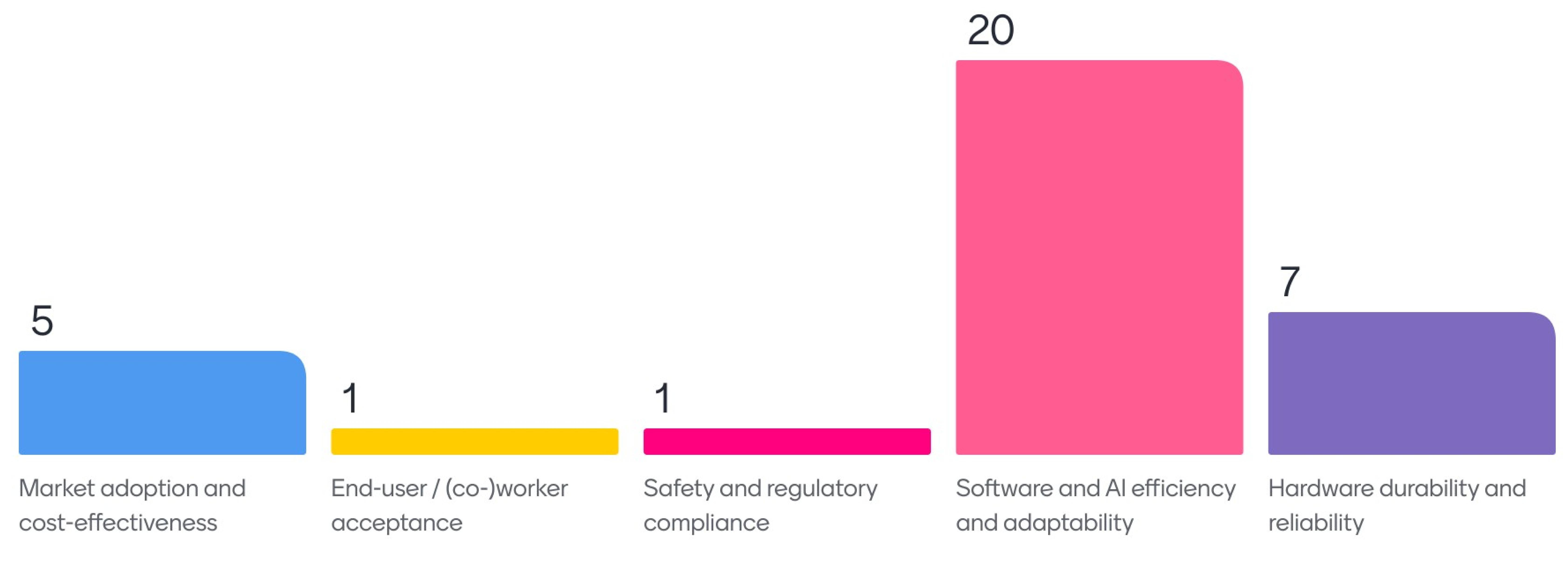






#### MANiBOT: Advancing the physical intelligence and performance of robots

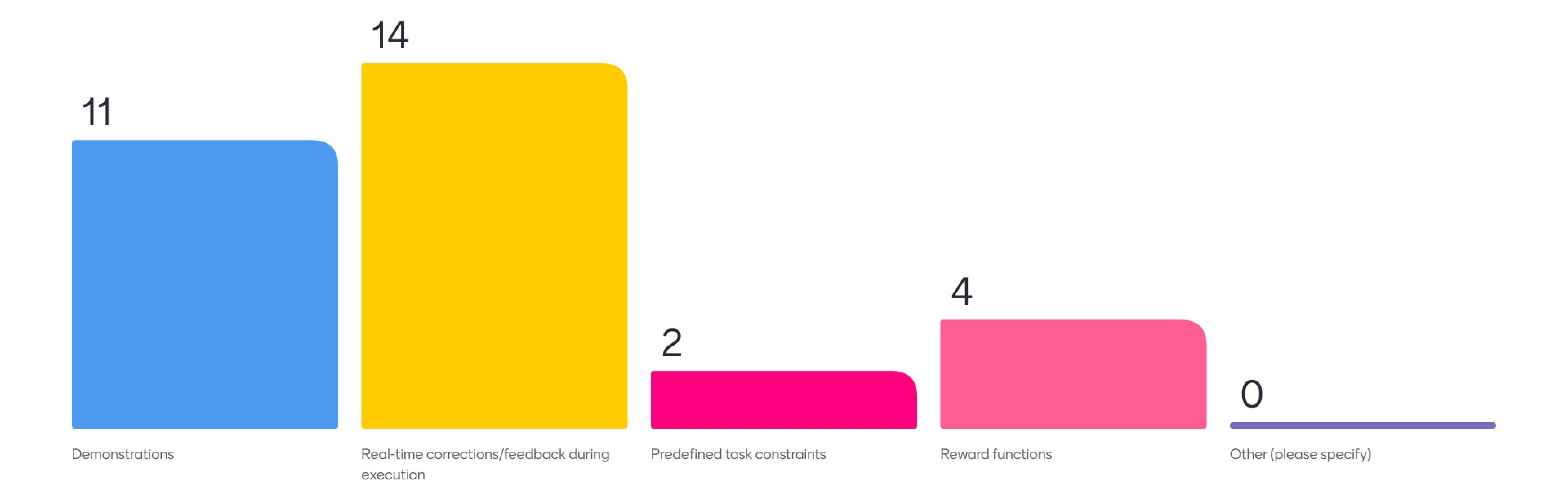
What do you see as the biggest challenge for robotic object manipulation systems that aim to address a wide range of very diverse objects?





Leveraging uncertainty and interactive guidance for robot skill acquisition

Which type of human input do you believe is the most practical for helping robots adapt to dynamic, real-world environments?





From the Lab to the Kitchen: Data-efficient Learning and Sim2Real

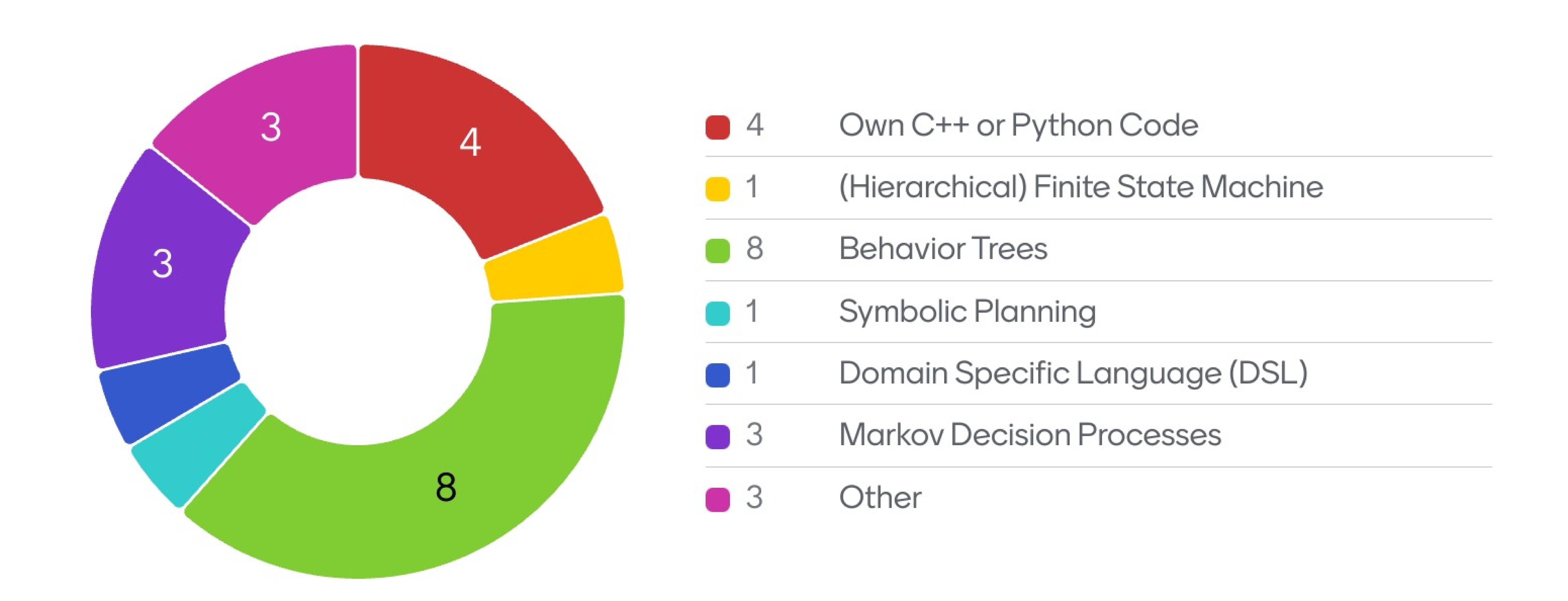
# What features would need to include design on robotic perception system that can reliably operate in a completely unknown kitchen environment?

27 responses

```
one shot manip skills
  open set segmentation
                              sensory motor integration
                                  object recognition
           interpretation skills
                                 common sense
            image recognition
                             compliant structure
                  sensors
                         thought building process
                stereo
           spatial vision conscious
                      awareness
                                   semantic
                 collision avoidance
                                              robust perception
                        quick virtual video tour
object handling capabilit
    domain knowledge
                           measure of uncertainty
             adaptable behavior
                                   semantic understanding
                        open world affordances
```



### What is your favorite tool for deliberation?





## Which questions would you like to ask our speakers?

What should be done to get the trust of industries on Aldriven robotic manipulation solutions?

Are the words conscious & deliberation the right words used in regards to the functionality the robots offer?

How can we design failure recovery mechanisms? With behaviour trees, in case one action (skill) fails, how can we "pause" the process to recover or ask the human intervene and then continue execution

Where do you see the largest challenges in your application case?

Will you upload the slides to the google drive?

The convince project sounds interesting, You mentioned that using model check to verify robot application. Does it means that we need to use DSL to create requirements? Is this top-down solution?

Feedback

**(optional)** Please provide your E-Mail if you want to learn about the results of this workshop. (Will be shared with the workshop organizers only)