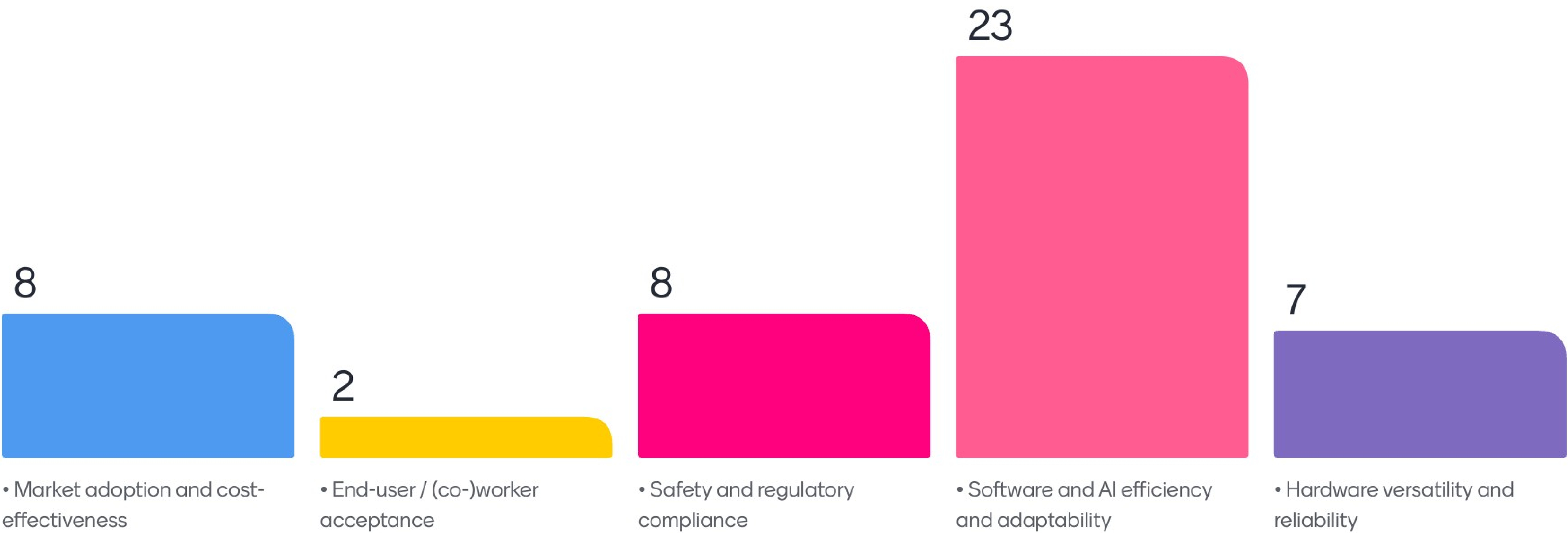
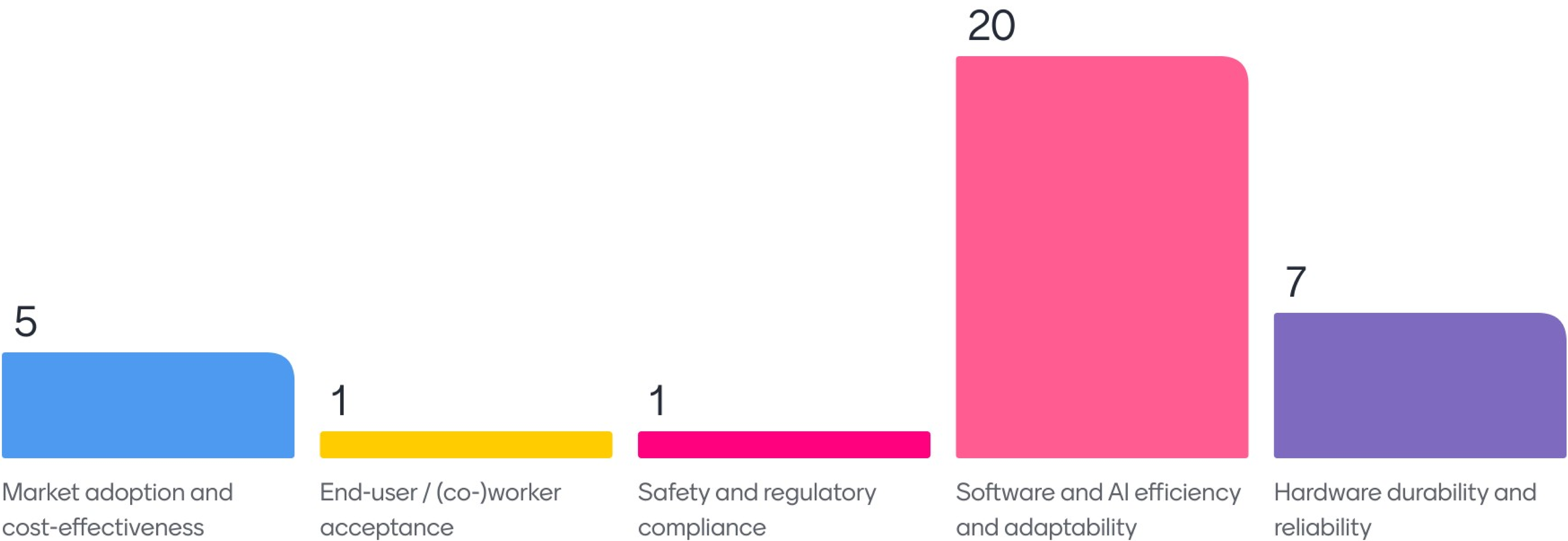


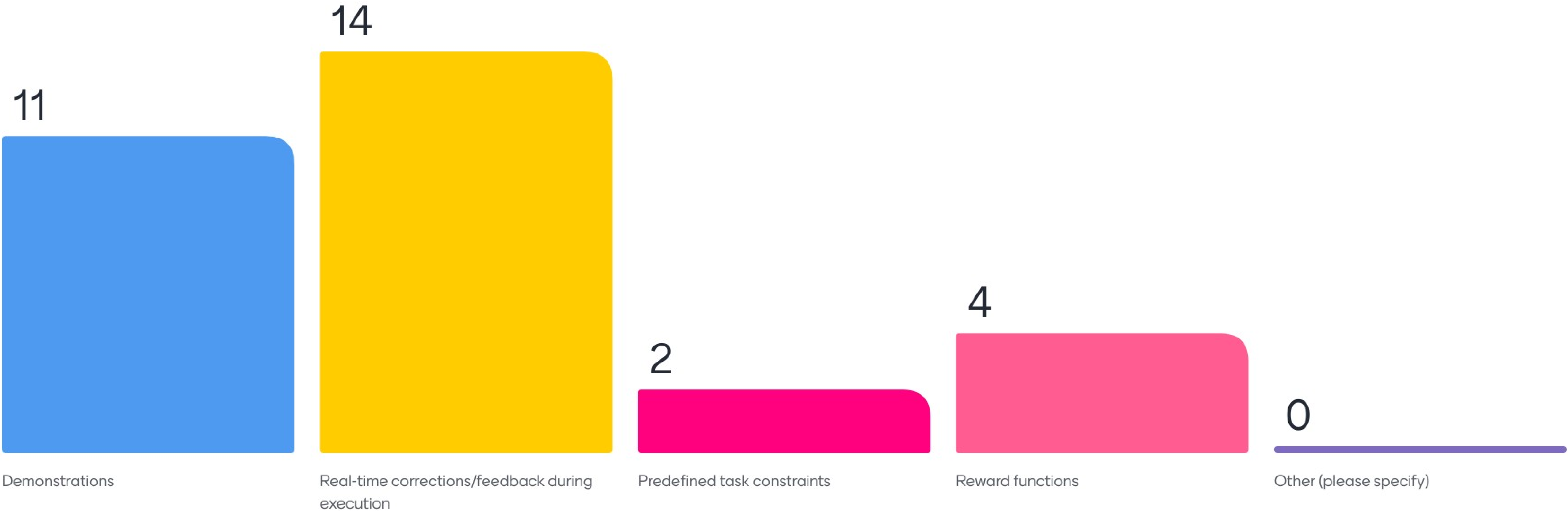
What do you see as the biggest challenge for enabling rapid skill learning in robotic manipulators designed to handle a wide variety of objects?



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



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



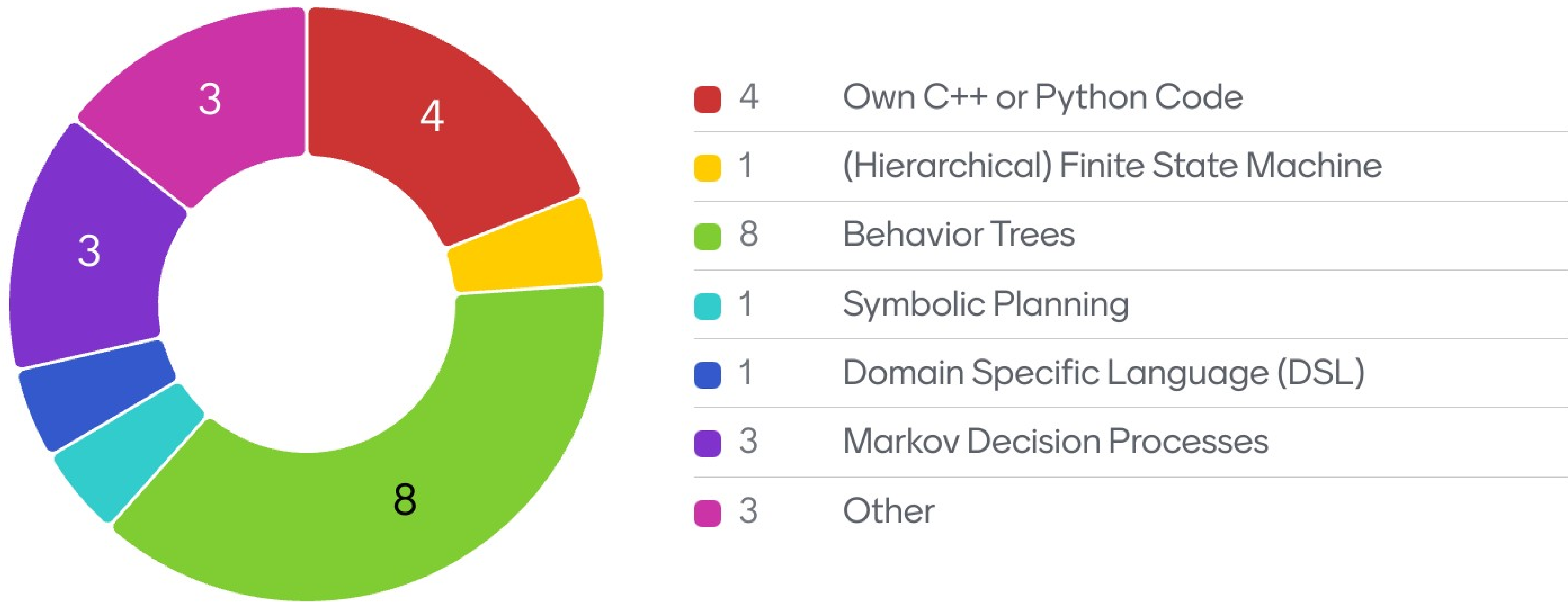
**What features would need to include design on robotic perception system that can reliably operate in a completely unknown kitchen environment?**

27 responses





# 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 AI-driven 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)