



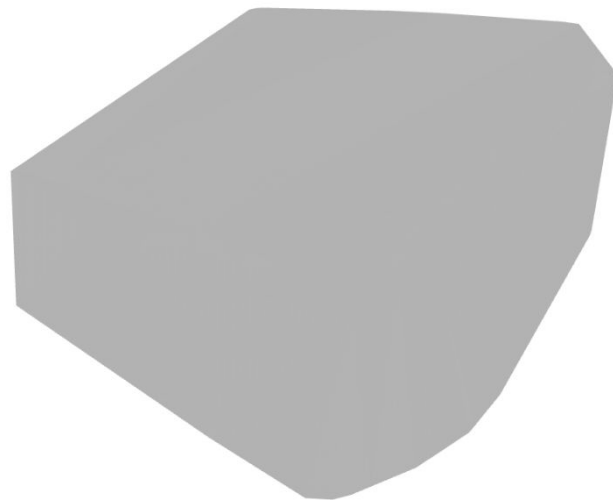
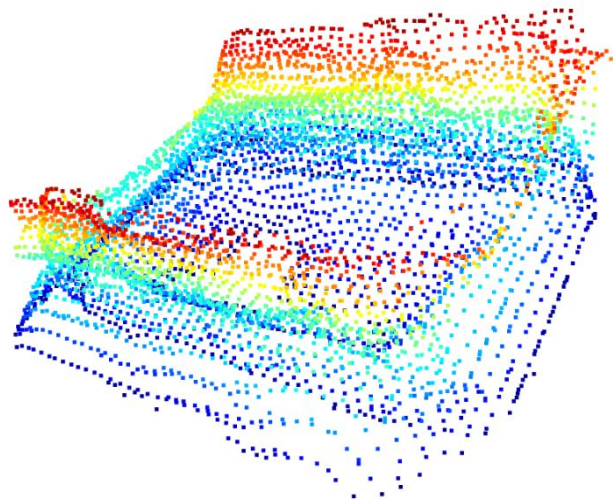
Grasping Assignment

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Point clouds using Open3D

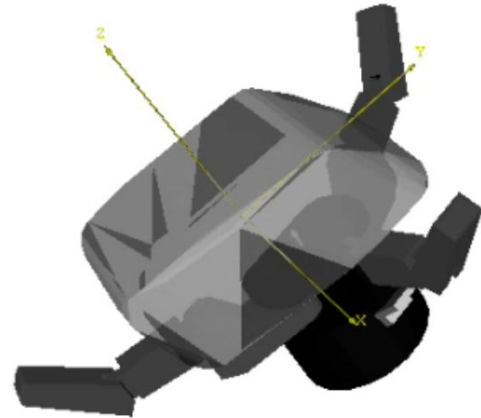
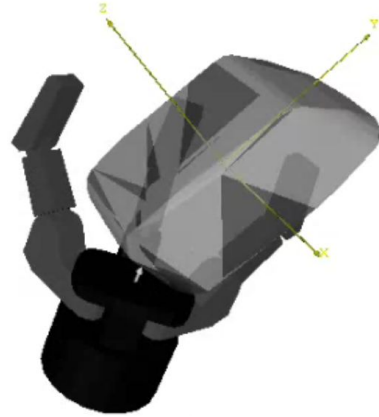
- `pcl_temp = o3d.io.read_point_cloud()`
- `o3d.visualization.draw_geometries()`



Graspt!

- `Plan = GraspitCommander.planGrasps()`

```
graspable_body_id: 0
pose:
  position:
    x: -0.21767949553698396
    y: 0.002949917777998241
    z: 0.0042690943373535056
  orientation:
    x: 0.7136441748665363
    y: -0.06336770596577597
    z: -0.052716884806794
    w: 0.6956417580737682
dofs: [1.313103297497527]
epsilon_quality: -1.0
volume_quality: 0.0
...
```



GPD

- Real Life Scenario - Objects are physically inaccessible due to contact from surfaces
- Modify bounding box of point cloud to include table

