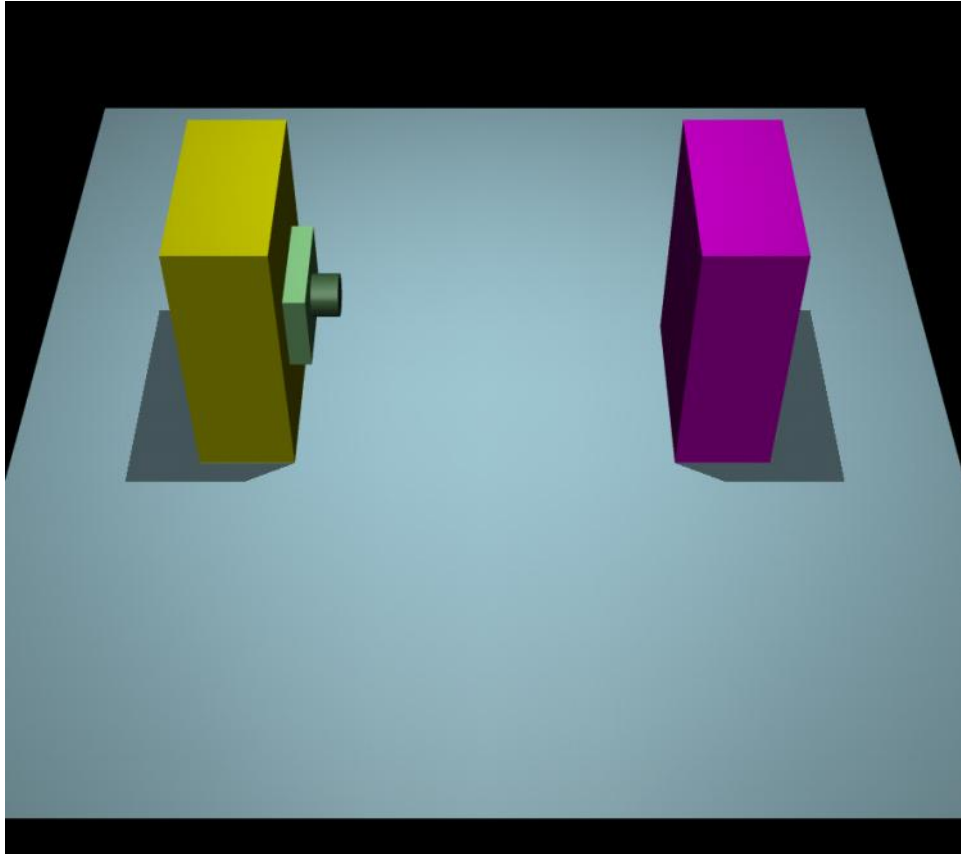
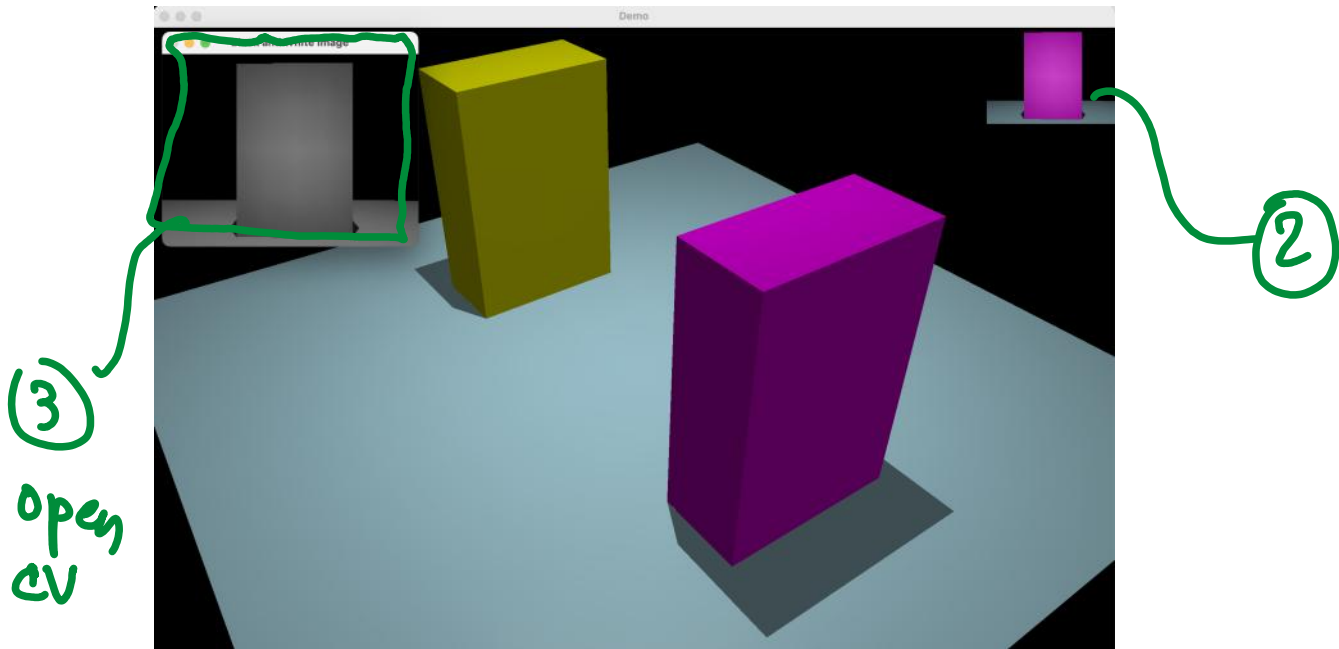


Camera Placement



1) setting up camera using mujoco viewer

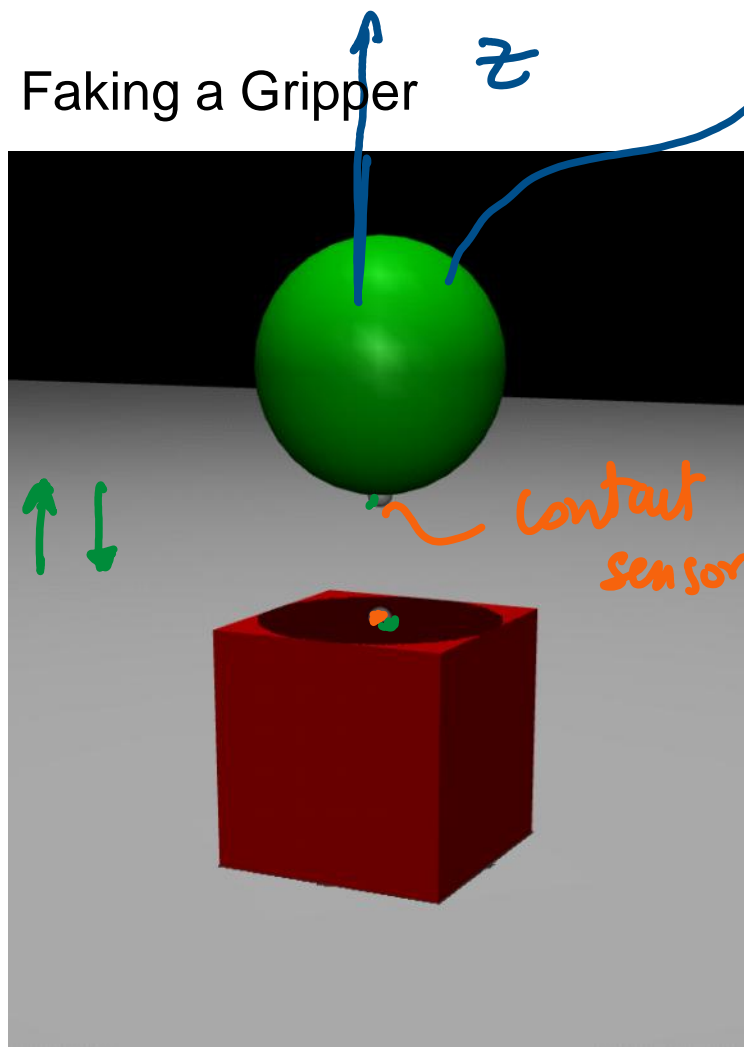
Camera



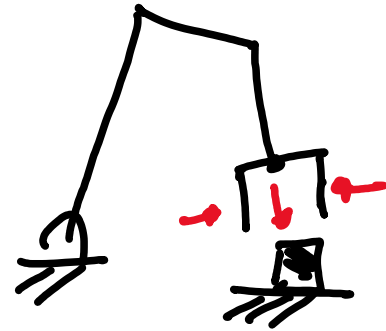
2) add inset view

3) using open cv for image manipulation

Faking a Gripper



end-effector



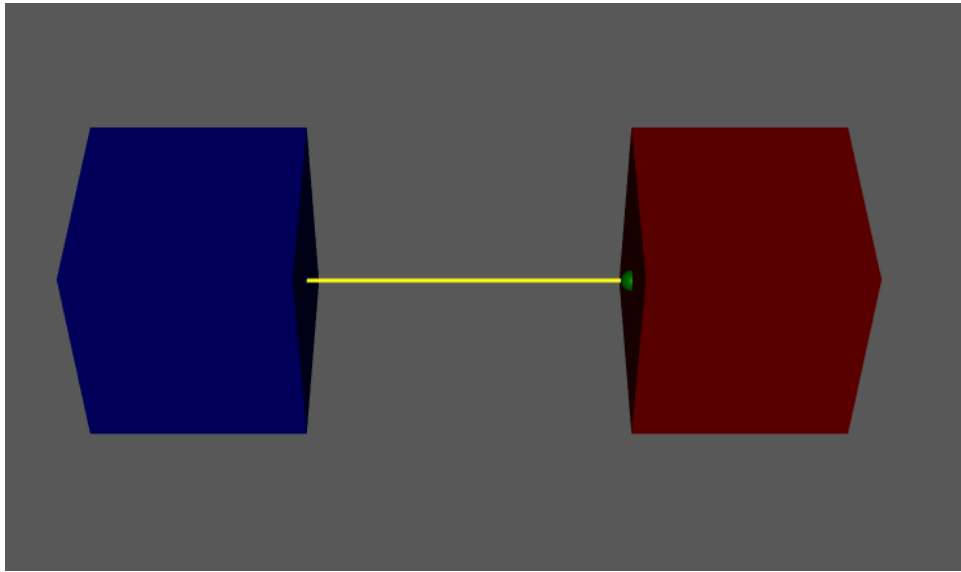
- friction

- poor placement of end-effector



- ✓ 1) finite state machine for end-effector and gripper
- ✓ control
- ✓ 2) touch sensor to sense contact between gripper and object.
- 3) equality to fake a gripper

Range Sensor



- 1) range sensor to detect proximity
- 2) adding noise
- 3) adding cut-off
- 4) filtering noise