
Hardware–software complex for solving the task of automatic capture of the object with manipulators

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The article presents a developed in BMSTU hardware and software package for modeling and testing robotic operations of capture and moving objects. It describes the structure, operation algorithms and software for solving problems of automatic capture of objects with the manipulator equipped with a gripper with tactile sensitization. Implementation of automatic capture of rectangular shape non-deformable objects is illustrated by examples.

Keywords: *working objects, automatic capture, grasp planning, gripper with tactile sensitization, computer vision system, pattern recognition, point cloud.*

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