Abstract

Initially, the emphasis of the robotic arm is placed on grasping and positioning objects in space. These types of robotic arms have a stake in planetary and underwater research, robotic surgery, systems for disabled people, households and so on. The strategy for grasping and positioning objects is based on recording environment with a web camera. Strategic decisions affect the orientation of the hand and the way of opening the gripper. At the same time, opening the gripper should match the shape and size of objects being used. The creation of a system based on this strategy, which then can be practically applied while being inexpensive and simple to implement, is the main goal of this paper.

References


**Index Terms**

Computer Science  
Artificial Intelligence
Keywords

Robotic arm, manipulator, grasping objects, segmentation, visual servoing