

UNIVERSITY OF SOUTH FLORIDA

Defense of a Master's Thesis

Predicting the Number of Objects in a Robotic Grasp

by

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Picking up the desired number of objects at once from a pile is still very difficult to do for a robot. The main challenge is predicting the number of objects in the grasp. This thesis describes several prediction models that predict the number of objects in the grasp of a Barrett hand using the tactile sensors and palm and its