

Simulated Robotic Manipulation Benchmark

Reference No / Version	RAL-SI-2020-P[19-0842]_1-V1.1 for the latest versions of the benchmark please refer to https://research.csiro.au/robotics/manipulation-benchmark/
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Adopted Protocol	Simulated Robotic Manipulation Protocol – Task1 (RAL-SI-2020-P[19-0842]_1-V1.1)
Scoring	<ul style="list-style-type: none"> For scoring, the following must be recorded at 10Hz throughout the duration of the simulation. This is to be exported to a csv with the following information to be recorded in the listed order: <ul style="list-style-type: none"> Position (x,y,z)* Rotation (w,x,y,z)* Joint Torques (J1,J2,J3,J4,J5,J6) Finger Rotations (Finger 1, Finger 2, Finger 3) Force (Fx,Fy,Fz)* Moments (Mx, My, Mz)* 20 Repeats of the simulation are required (used to determine if the simulator is deterministic) Use the performance_metric.py script which can be found at https://research.csiro.au/robotics/manipulation-benchmark/ to generate results. Sum errors for each of the following categories for all tasks in a subgroup: Euclidean distance, rotation, pose, velocity, acceleration, torque, force, moments. <p><i>*From the 'Measurement Frame' as listed in Figures 1 and 2 in the protocol (also referred to as the 'ft_mount_measurement_joint' in the URDF).</i></p>
Details of Setup	<ul style="list-style-type: none"> Detailed information on: <ul style="list-style-type: none"> Simulator/Physics Engine used; Tuned parameters and their values; and Anything else required to reproduce results.
Results to Submit	<ul style="list-style-type: none"> CSV files from all 20 repeats as used for scoring. CSV files for all other tasks from subgroup 1 (i.e. Task 2).