IN-HAND MANIPULATION BENCHMARK

Reference No / Version	RAL-SI-2020-B19-0827-V1.0 for the latest versions of the benchmark, please refer to https://robot-learning.cs.utah.edu/project/benchmarking_in_hand_manipulation
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Adopted Protocol	In-Hand Manipulation Protocol
Scoring	The scoring is based on the distance from the desired hand pose and the distance from the desired contact points. For more details, refer to section II.A of the benchmark article.
Details of Setup	Report the used robotic platform and any additional information about the experimental setup. Any modifications made to the object from the YCB dataset or the robot's gripper need to be reported
Results to Submit	The following results must be submitted. Refer to section II.C in the article for more details. The error between the given initial hand pose and the actual hand pose; The error between the desired grasp and the reached grasp; The time spent to plan and execute in-hand manipulation; The percentage of executions in which the object was dropped (i.e. unsuccessful executions).