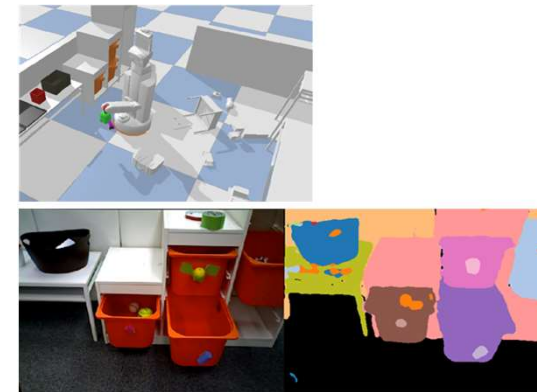


# Team Weblab (Japan)



## Development point

Aiming to achieve flexible control within a home environment, we make extensive use of machine learning modules. In particular, we use data generated by simulation to learn deep learning models for estimating grasp pose & furniture (sim2real). We have also devised a system design to efficiently execute such deep learning modules.



## Introduction of your team

**[Inspiration & Motivation]** The goal is implementing a robot system which can work on many kind of environments and edge cases. We aim to realize flexible and adaptive service-robot by mainly using data-driven methods, not using complex heuristic methods.

**[Future outlook]** We aim to implement more flexible, adaptive and robust service-robot and to find the efficient ways to take a large amount of training-data.

Role	Name	Affiliation/Title	Specialty, Field of study
Team leader	Tatsuya Matsushima	UTokyo, Ph.D student	Robot learning
Recognition	Yuki Noguchi	UTokyo, Master's student	Robot learning
System Design	Jumpei Arima	Toyota Motor Corporation	Autonomous navigation, Robot system
System Design	Toshiki Aoki	UTokyo, Undergraduate	HCI, Computer graphics
Recognition	Yuki Okita	UTokyo, Master's student	Continuous optimization
Recognition	Yuya Ikeda	UTokyo, Undergraduate	Robot learning
Hardware	Koki Ishimoto	UTokyo, Master's student	Mechaprototyping, HRI
Recognition	Shohei Taniguchi	UTokyo, Ph.D student	Robot learning, Generative models
Recognition	Yuki Yamashita	UTokyo, Master's student	Computer vision
System Design	Shoichi Seto	UTokyo, Undergraduate	Embedded system, Control

