Development of intuitive teaching interface for shared-autonomous grasping control

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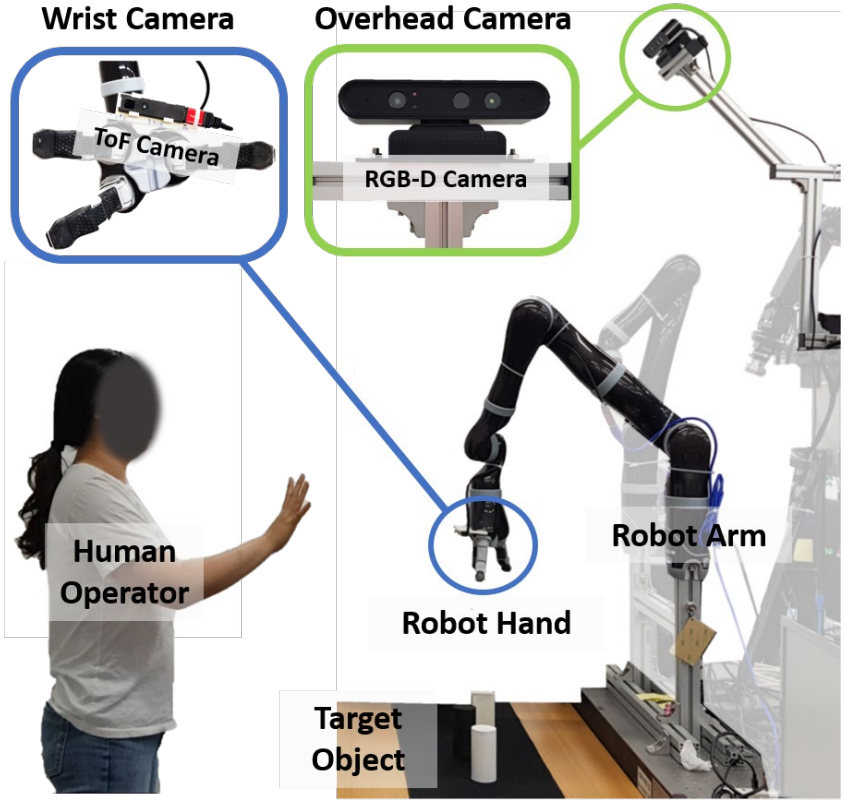

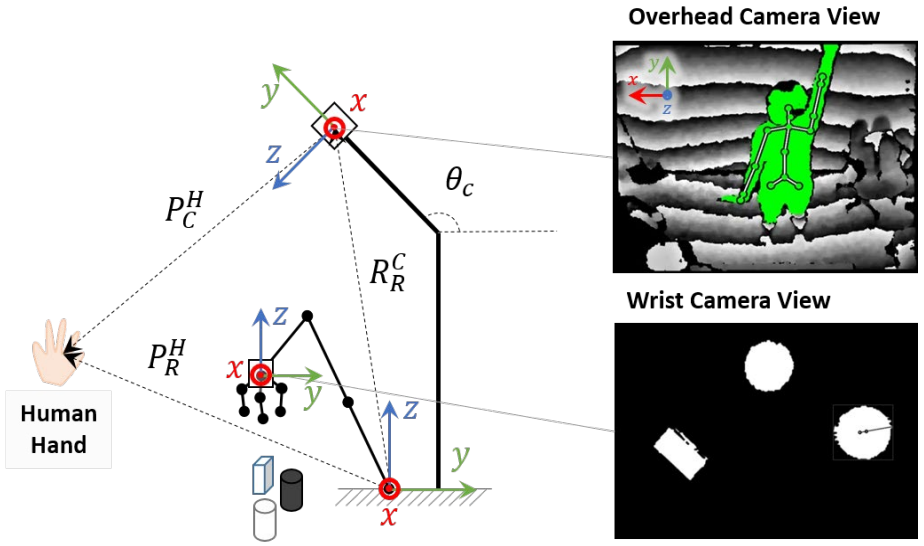

$$P_R^H = Q_x(\theta_c)P_C^H + R_R^C, \quad Q_x = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(\theta_c) & \sin(\theta_c) \\ 0 & -\sin(\theta_c) & \cos(\theta_c) \end{bmatrix}, \theta_c = -\frac{3}{4}\pi$$

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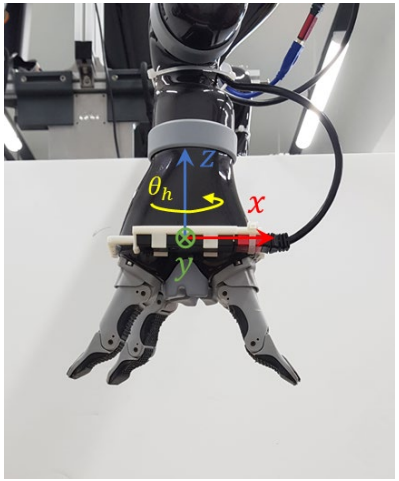

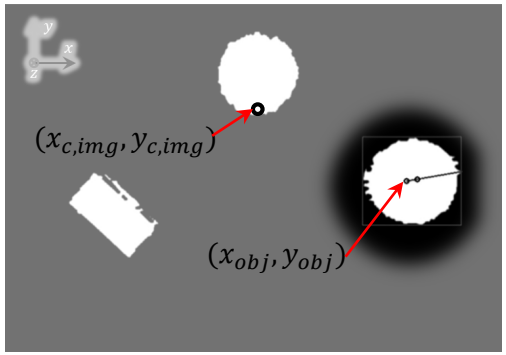

$$\Delta x_R = a_x * \left(x_{obj}/x_{c,img} - 1\right) * 0.01$$
$$\Delta y_R = -a_y * \left(y_{obj}/y_{c,img} - 1\right) * 0.01$$