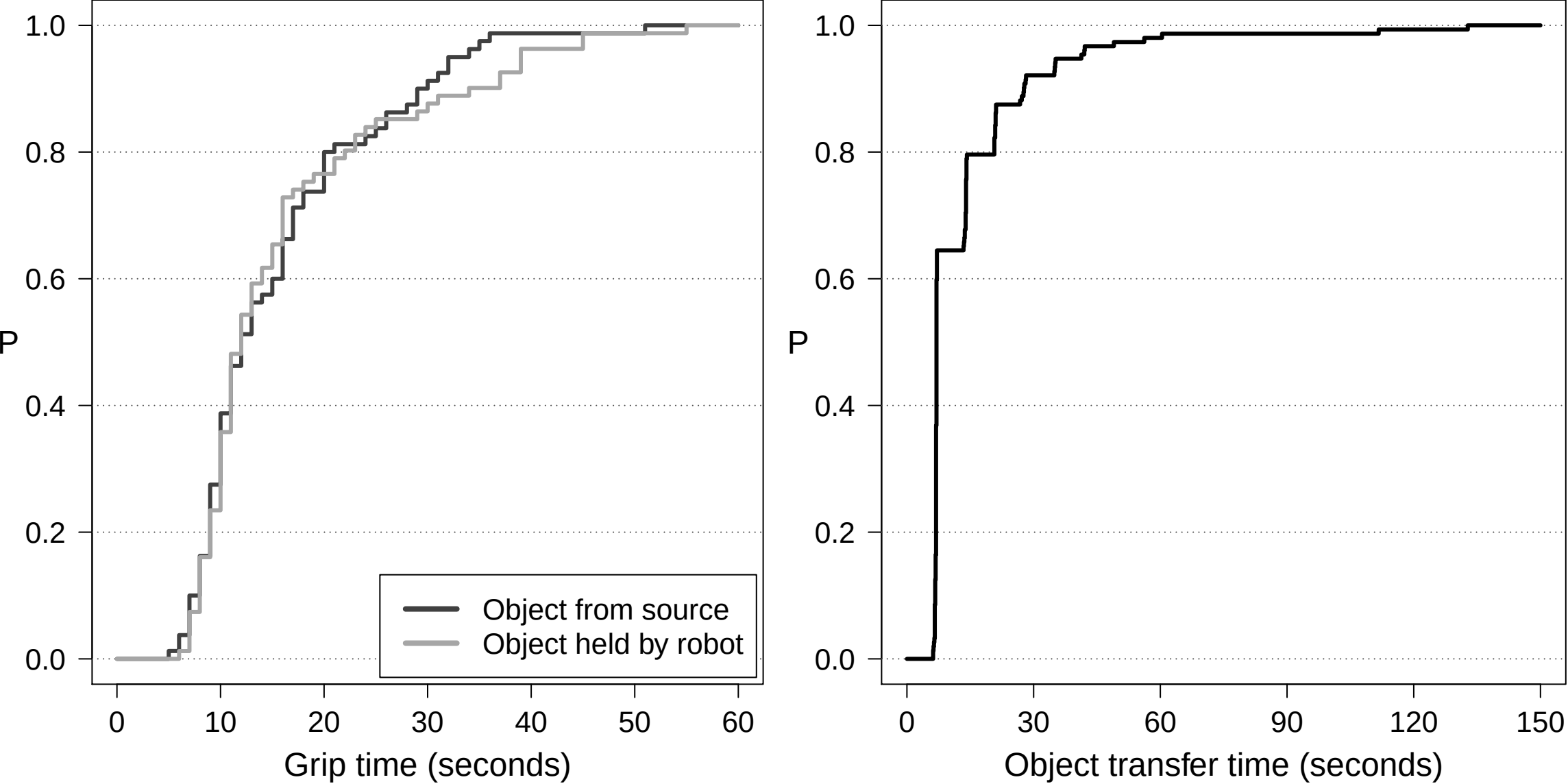
1.0
0.8
0.6
0.4
0.2
0.0
P
0
10
20
30
40
50
60
Grip time (seconds)
Object from source
Object held by robot
1.0
0.8
0.6
0.4
0.2
0.0
P
0
30
60
90
120
150
Object transfer time (seconds)