

# Solystic project idea

## (Cognition and control in complex systems)

**Operator loads and prepares the stack**

- Empiric gestures
- Various skills

**Could we transfer this knowledge to the robot ?**

**Stack of aggregated objects of different nature, dimensions, weight, material**

**Could we capture the dynamic of the stack ?**



**Complex « robot » to destack the objects into the machine**

- low interaction with the operator
- low knowledge of the stack content

**Could we replace this arm ?**