

Global Grasp Policy Model Market 2026 by Company, Regions, Type and Application, Forecast to 2032

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Abstracts

According to our (Global Info Research) latest study, the global Grasp Policy Model market size was valued at US\$ 1749 million in 2025 and is forecast to a readjusted size of US\$ 9891 million by 2032 with a CAGR of 24.5% during review period.

A grasp policy model is an intelligent decision-making model for robotic end effectors. Its core task is to convert vision, 3D point clouds, force sensing, tactile sensing, and task semantics into executable grasping actions in cluttered, occluded, mixed, transparent, reflective, flexible, or shape-uncertain object environments. This type of model usually performs object recognition, instance segmentation, pose estimation, grasp point generation, collision checking, path planning, tool selection, and failure retry, and outputs grasp points, six-degree-of-freedom poses, end-effector opening parameters, suction locations, approach angles, action sequences, or task-level policies, enabling robots to perform stable picking and placing without item-by-item manual teaching. Typical applications include e-commerce item piece picking, warehouse parcel induction, industrial bin picking, carton depalletizing, production line feeding, food packaging, and service robot object retrieval. Major customers include logistics automation integrators, industrial robot manufacturers, manufacturing companies, e-commerce fulfillment centers, robotic software platform providers, and research institutions. Common delivery forms include software modules, robot controller plug-ins, edge inference devices, vision-based grasping kits, complete workstation solutions, and subscription-based model upgrades.

The industrial value of grasp policy models is expanding from a single grasp-point algorithm into a core software layer for flexible robotic operations. Traditional industrial robots depend on fixed fixtures, predictable materials, and manual teaching, which makes them suitable for highly repetitive and structured production lines. However, in e-

commerce fulfillment, mixed parcels, randomly stacked materials, and high-mix low-volume manufacturing, object shape, position, orientation, material, and occlusion constantly change, making it difficult for taught paths alone to ensure efficiency and stability. By combining visual perception, 3D point clouds, semantic recognition, grasp pose generation, collision checking, path planning, and failure retry, grasp policy models convert environmental information into executable robotic actions and enable robots to pick and place autonomously in unknown-object and unstructured scenarios. As foundation models, simulation training, and edge inference continue to improve, grasp models are likely to evolve from standalone software modules into a transferable policy layer across devices, grippers, and scenarios, performing a brain-like decision-making role within robotic workstations. This trend will increase the software value share of robotic systems and shift competition toward data accumulation, model generalization, interface openness, and on-site closed-loop optimization.

From an application perspective, warehouse logistics and industrial bin picking are the two scenarios where grasp policy models are first forming scalable demand. In warehouse logistics, item piece picking, parcel induction, packing, sorting, and depalletizing involve high SKU diversity, order volatility, high labor intensity, and unstable labor supply, creating strong demand for autonomous recognition, rapid decision-making, and stable grasping. In industrial settings, bin picking, machine tending, assembly feeding, and production-line transfer place greater emphasis on random pile recognition, reflective metal-part handling, accurate grasp poses, collision avoidance, and cycle-time stability. Although the two scenarios serve different downstream industries, both require the model to quickly output executable actions from complex visual inputs and automatically adjust its strategy when a grasp fails, occlusion changes, or an object shifts. As enterprises move from point automation toward flexible production lines and intelligent warehousing, the grasp policy model is no longer an auxiliary function of a robotic workstation, but a key module that determines deployable scope, maintenance cost, yield, and return on investment. Models with no-teach, few-shot learning, real-time replanning, and multi-end-effector adaptation capabilities will be easier to replicate across industries.

From a competitive landscape perspective, grasp policy models are forming a multilayer ecosystem involving platform companies, robotic system providers, vision software companies, and end-effector manufacturers. Platform companies focus more on foundation models, simulation environments, developer tools, and cross-robot deployment. System providers emphasize complete workstation delivery, cycle-time optimization, and field reliability. Vision software companies focus on object recognition, pose estimation, point-cloud processing, and grasp-point output. End-effector

manufacturers combine grasp models with grippers, suction cups, force control, and control interfaces to improve hardware intelligence. In the short term, the market will remain dominated by project integration and industry solutions because object types, containers, cycle times, and safety requirements vary significantly across scenarios. In the medium to long term, as model generalization, interface standardization, and simulation data mature, grasp policy models are expected to become reusable software modules and generate recurring revenue through subscription licensing, edge deployment, and cloud-based model upgrades. Growth in this field will come not only from new robot installations, but also from intelligent retrofits of existing robotic lines and deeper automation penetration in high-mix scenarios.

This report is a detailed and comprehensive analysis for global Grasp Policy Model market. Both quantitative and qualitative analyses are presented by company, by region & country, by Perception Input and by Application. As the market is constantly changing, this report explores the competition, supply and demand trends, as well as key factors that contribute to its changing demands across many markets. Company profiles and product examples of selected competitors, along with market share estimates of some of the selected leaders for the year 2025, are provided.

Key Features:

Global Grasp Policy Model market size and forecasts, in consumption value (\$ Million), 2021-2032

Global Grasp Policy Model market size and forecasts by region and country, in consumption value (\$ Million), 2021-2032

Global Grasp Policy Model market size and forecasts, by Perception Input and by Application, in consumption value (\$ Million), 2021-2032

Global Grasp Policy Model market shares of main players, in revenue (\$ Million), 2021-2026

The Primary Objectives in This Report Are:

To determine the size of the total market opportunity of global and key countries

To assess the growth potential for Grasp Policy Model

To forecast future growth in each product and end-use market

To assess competitive factors affecting the marketplace

This report profiles key players in the global Grasp Policy Model market based on the following parameters - company overview, revenue, gross margin, product portfolio, geographical presence, and key developments. Key companies covered as a part of this study include NVIDIA Corporation, Intrinsic Innovation LLC, Covariant AI, Inc., OSARO, Inc., Plus One Robotics, Inc., RightHand Robotics, Inc., Mujin, Inc., KUKA AG, Festo SE & Co. KG, SCHUNK SE & Co. KG, etc.

This report also provides key insights about market drivers, restraints, opportunities, new product launches or approvals.

Market segmentation

Grasp Policy Model market is split by Perception Input and by Application. For the period 2021-2032, the growth among segments provides accurate calculations and forecasts for Consumption Value by Perception Input and by Application. This analysis can help you expand your business by targeting qualified niche markets.

Market segment by Perception Input

2D Vision Model

3D Point Cloud Model

Multimodal Vision Model

Tactile Force-Control Model

Other

Market segment by Decision Paradigm

Rule-Based Geometric Model

Supervised Learning Model

Reinforcement Learning Model

Imitation Learning Model

Generative Diffusion Model

Foundation Model

Market segment by Control Loop

Open-Loop Grasping Model

Visual Closed-Loop Model

Force-Sensing Closed-Loop Model

Vision-Tactile Fusion Closed-Loop Model

Market segment by Target Object State

Regular Rigid Object Model

Cluttered Stacked Object Model

Transparent and Reflective Object Model

Flexible Packaging Object Model

Entangled Wire Harness Object Model

Other

Market segment by Application

Item Piece Picking

Industrial Bin Picking

Carton Depalletizing

Parcel Induction

Assembly Feeding

Service Object Retrieval

Other

Market segment by players, this report covers

NVIDIA Corporation

Intrinsic Innovation LLC

Covariant AI, Inc.

OSARO, Inc.

Plus One Robotics, Inc.

RightHand Robotics, Inc.

Mujin, Inc.

KUKA AG

Festo SE & Co. KG

SCHUNK SE & Co. KG

Basler AG

Roboception GmbH

Apera AI Inc.

Realtime Robotics, Inc.

Mech-Mind Robotics

XYZ Robotics

Dobot Robotics

Market segment by regions, regional analysis covers

North America (United States, Canada and Mexico)

Europe (Germany, France, UK, Russia, Italy and Rest of Europe)

Asia-Pacific (China, Japan, South Korea, India, Southeast Asia and Rest of Asia-Pacific)

South America (Brazil, Rest of South America)

Middle East & Africa (Turkey, Saudi Arabia, UAE, Rest of Middle East & Africa)

The content of the study subjects, includes a total of 13 chapters:

Chapter 1, to describe Grasp Policy Model product scope, market overview, market estimation caveats and base year.

Chapter 2, to profile the top players of Grasp Policy Model, with revenue, gross margin, and global market share of Grasp Policy Model from 2021 to 2026.

Chapter 3, the Grasp Policy Model competitive situation, revenue, and global market share of top players are analyzed emphatically by landscape contrast.

Chapter 4 and 5, to segment the market size by Perception Input and by Application, with consumption value and growth rate by Perception Input, by Application, from 2021

to 2032.

Chapter 6, 7, 8, 9, and 10, to break the market size data at the country level, with revenue and market share for key countries in the world, from 2021 to 2026. and Grasp Policy Model market forecast, by regions, by Perception Input and by Application, with consumption value, from 2027 to 2032.

Chapter 11, market dynamics, drivers, restraints, trends, Porters Five Forces analysis.

Chapter 12, the key raw materials and key suppliers, and industry chain of Grasp Policy Model.

Chapter 13, to describe Grasp Policy Model research findings and conclusion.

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