

Global Grasp Policy Model Supply, Demand and Key Producers, 2026-2032

<https://marketpublishers.com/r/GA4DF563161CEN.html>

Date: August 2026

Pages: 138

Price: US\$ 4,480.00 (Single User License)

ID: GA4DF563161CEN

Abstracts

The global Grasp Policy Model market size is expected to reach \$ 9891 million by 2032, rising at a market growth of 24.5% CAGR during the forecast period (2026-2032).

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 studies the global Grasp Policy Model demand, key companies, and key regions.

This report is a detailed and comprehensive analysis of the world market for Grasp Policy Model, and provides market size (US\$ million) and Year-over-Year (YoY) growth, considering 2025 as the base year. This report explores demand trends and competition, as well as details the characteristics of Grasp Policy Model that contribute to its increasing demand across many markets.

Highlights and key features of the study

Global Grasp Policy Model total market, 2021-2032, (USD Million)

Global Grasp Policy Model total market by region & country, CAGR, 2021-2032, (USD Million)

U.S. VS China: Grasp Policy Model total market, key domestic companies, and share, (USD Million)

Global Grasp Policy Model revenue by player, revenue and market share 2021-2026, (USD Million)

Global Grasp Policy Model total market by Perception Input, CAGR, 2021-2032, (USD Million)

Global Grasp Policy Model total market by Application, CAGR, 2021-2032, (USD Million)

This report profiles major 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.

Stakeholders would have ease in decision-making through various strategy matrices used in analyzing the world Grasp Policy Model market

Detailed Segmentation:

Each section contains quantitative market data including market by value (US\$ Millions), by player, by regions, by Perception Input, and by Application. Data is given for the years 2021-2032 by year with 2025 as the base year, 2026 as the estimate year, and 2027-2032 as the forecast year.

Global Grasp Policy Model Market, By Region:

United States

China

Europe

Japan

South Korea

ASEAN

India

Rest of World

Global Grasp Policy Model Market, Segmentation by Perception Input:

2D Vision Model

3D Point Cloud Model

Multimodal Vision Model

Tactile Force-Control Model

Other

Global Grasp Policy Model Market, Segmentation by Decision Paradigm:

Rule-Based Geometric Model

Supervised Learning Model

Reinforcement Learning Model

Imitation Learning Model

Generative Diffusion Model

Foundation Model

Global Grasp Policy Model Market, Segmentation by Control Loop:

Open-Loop Grasping Model

Visual Closed-Loop Model

Force-Sensing Closed-Loop Model

Vision-Tactile Fusion Closed-Loop Model

Global Grasp Policy Model Market, Segmentation 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

Global Grasp Policy Model Market, Segmentation by Application:

Item Piece Picking

Industrial Bin Picking

Carton Depalletizing

Parcel Induction

Assembly Feeding

Service Object Retrieval

Other

Companies Profiled:

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

Key Questions Answered

1. How big is the global Grasp Policy Model market?
2. What is the demand of the global Grasp Policy Model market?
3. What is the year over year growth of the global Grasp Policy Model market?
4. What is the total value of the global Grasp Policy Model market?
5. Who are the Major Players in the global Grasp Policy Model market?
6. What are the growth factors driving the market demand?

Contents

1 SUPPLY SUMMARY

- 1.1 Grasp Policy Model Introduction
- 1.2 World Grasp Policy Model Market Size & Forecast (2021 & 2025 & 2032)
- 1.3 World Grasp Policy Model Total Market by Region (by Headquarter Location)
 - 1.3.1 World Grasp Policy Model Market Size by Region (2021-2032), (by Headquarter Location)
 - 1.3.2 United States Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.3 China Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.4 Europe Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.5 Japan Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.6 South Korea Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.7 ASEAN Based Company Grasp Policy Model Revenue (2021-2032)
 - 1.3.8 India Based Company Grasp Policy Model Revenue (2021-2032)
- 1.4 Market Drivers, Restraints and Trends
 - 1.4.1 Grasp Policy Model Market Drivers
 - 1.4.2 Factors Affecting Demand
 - 1.4.3 Major Market Trends

2 DEMAND SUMMARY

- 2.1 World Grasp Policy Model Consumption Value (2021-2032)
- 2.2 World Grasp Policy Model Consumption Value by Region
 - 2.2.1 World Grasp Policy Model Consumption Value by Region (2021-2026)
 - 2.2.2 World Grasp Policy Model Consumption Value Forecast by Region (2027-2032)
- 2.3 United States Grasp Policy Model Consumption Value (2021-2032)
- 2.4 China Grasp Policy Model Consumption Value (2021-2032)
- 2.5 Europe Grasp Policy Model Consumption Value (2021-2032)
- 2.6 Japan Grasp Policy Model Consumption Value (2021-2032)
- 2.7 South Korea Grasp Policy Model Consumption Value (2021-2032)
- 2.8 ASEAN Grasp Policy Model Consumption Value (2021-2032)
- 2.9 India Grasp Policy Model Consumption Value (2021-2032)

3 WORLD GRASP POLICY MODEL COMPANIES COMPETITIVE ANALYSIS

- 3.1 World Grasp Policy Model Revenue by Player (2021-2026)
- 3.2 Industry Rank and Concentration Rate (CR)

- 3.2.1 Global Grasp Policy Model Industry Rank of Major Players
- 3.2.2 Global Concentration Ratios (CR4) for Grasp Policy Model in 2025
- 3.2.3 Global Concentration Ratios (CR8) for Grasp Policy Model in 2025
- 3.3 Grasp Policy Model Company Evaluation Quadrant
- 3.4 Grasp Policy Model Market: Overall Company Footprint Analysis
 - 3.4.1 Grasp Policy Model Market: Region Footprint
 - 3.4.2 Grasp Policy Model Market: Company Product Type Footprint
 - 3.4.3 Grasp Policy Model Market: Company Product Application Footprint
- 3.5 Competitive Environment
 - 3.5.1 Historical Structure of the Industry
 - 3.5.2 Barriers of Market Entry
 - 3.5.3 Factors of Competition
- 3.6 Mergers & Acquisitions Activity

4 UNITED STATES VS CHINA VS REST OF WORLD (BY HEADQUARTER LOCATION)

- 4.1 United States VS China: Grasp Policy Model Revenue Comparison (by Headquarter Location)
 - 4.1.1 United States VS China: Grasp Policy Model Revenue Comparison (2021 & 2025 & 2032) (by Headquarter Location)
 - 4.1.2 United States VS China: Grasp Policy Model Revenue Market Share Comparison (2021 & 2025 & 2032)
- 4.2 United States Based Companies VS China Based Companies: Grasp Policy Model Consumption Value Comparison
 - 4.2.1 United States VS China: Grasp Policy Model Consumption Value Comparison (2021 & 2025 & 2032)
 - 4.2.2 United States VS China: Grasp Policy Model Consumption Value Market Share Comparison (2021 & 2025 & 2032)
- 4.3 United States Based Grasp Policy Model Companies and Market Share, 2021-2026
 - 4.3.1 United States Based Grasp Policy Model Companies, Headquarters (States, Country)
 - 4.3.2 United States Based Companies Grasp Policy Model Revenue, (2021-2026)
- 4.4 China Based Companies Grasp Policy Model Revenue and Market Share, 2021-2026
 - 4.4.1 China Based Grasp Policy Model Companies, Company Headquarters (Province, Country)
 - 4.4.2 China Based Companies Grasp Policy Model Revenue, (2021-2026)
- 4.5 Rest of World Based Grasp Policy Model Companies and Market Share, 2021-2026

4.5.1 Rest of World Based Grasp Policy Model Companies, Headquarters (Province, Country)

4.5.2 Rest of World Based Companies Grasp Policy Model Revenue (2021-2026)

5 MARKET ANALYSIS BY PERCEPTION INPUT

5.1 World Grasp Policy Model Market Size Overview by Perception Input: 2021 VS 2025 VS 2032

5.2 Segment Introduction by Perception Input

5.2.1 2D Vision Model

5.2.2 3D Point Cloud Model

5.2.3 Multimodal Vision Model

5.2.4 Tactile Force-Control Model

5.2.5 Other

5.3 Market Segment by Perception Input

5.3.1 World Grasp Policy Model Market Size by Perception Input (2021-2026)

5.3.2 World Grasp Policy Model Market Size by Perception Input (2027-2032)

5.3.3 World Grasp Policy Model Market Size Market Share by Perception Input (2027-2032)

6 MARKET ANALYSIS BY DECISION PARADIGM

6.1 World Grasp Policy Model Market Size Overview by Decision Paradigm: 2021 VS 2025 VS 2032

6.2 Segment Introduction by Decision Paradigm

6.2.1 Rule-Based Geometric Model

6.2.2 Supervised Learning Model

6.2.3 Reinforcement Learning Model

6.2.4 Imitation Learning Model

6.2.5 Generative Diffusion Model

6.2.6 Foundation Model

6.3 Market Segment by Decision Paradigm

6.3.1 World Grasp Policy Model Market Size by Decision Paradigm (2021-2026)

6.3.2 World Grasp Policy Model Market Size by Decision Paradigm (2027-2032)

6.3.3 World Grasp Policy Model Market Size Market Share by Decision Paradigm (2027-2032)

7 MARKET ANALYSIS BY CONTROL LOOP

7.1 World Grasp Policy Model Market Size Overview by Control Loop: 2021 VS 2025 VS 2032

7.2 Segment Introduction by Control Loop

7.2.1 Open-Loop Grasping Model

7.2.2 Visual Closed-Loop Model

7.2.3 Force-Sensing Closed-Loop Model

7.2.4 Vision-Tactile Fusion Closed-Loop Model

7.3 Market Segment by Control Loop

7.3.1 World Grasp Policy Model Market Size by Control Loop (2021-2026)

7.3.2 World Grasp Policy Model Market Size by Control Loop (2027-2032)

7.3.3 World Grasp Policy Model Market Size Market Share by Control Loop (2027-2032)

8 MARKET ANALYSIS BY TARGET OBJECT STATE

8.1 World Grasp Policy Model Market Size Overview by Target Object State: 2021 VS 2025 VS 2032

8.2 Segment Introduction by Target Object State

8.2.1 Regular Rigid Object Model

8.2.2 Cluttered Stacked Object Model

8.2.3 Transparent and Reflective Object Model

8.2.4 Flexible Packaging Object Model

8.2.5 Entangled Wire Harness Object Model

8.2.6 Other

8.3 Market Segment by Target Object State

8.3.1 World Grasp Policy Model Market Size by Target Object State (2021-2026)

8.3.2 World Grasp Policy Model Market Size by Target Object State (2027-2032)

8.3.3 World Grasp Policy Model Market Size Market Share by Target Object State (2027-2032)

9 MARKET ANALYSIS BY APPLICATION

9.1 World Grasp Policy Model Market Size Overview by Application: 2021 VS 2025 VS 2032

9.2 Segment Introduction by Application

9.2.1 Item Piece Picking

9.2.2 Industrial Bin Picking

9.2.3 Carton Depalletizing

9.2.4 Parcel Induction

9.2.5 Assembly Feeding

9.2.6 Service Object Retrieval

9.2.7 Other

9.3 Market Segment by Application

9.3.1 World Grasp Policy Model Market Size by Application (2021-2026)

9.3.2 World Grasp Policy Model Market Size by Application (2027-2032)

9.3.3 World Grasp Policy Model Market Size Market Share by Application (2021-2032)

10 COMPANY PROFILES

10.1 NVIDIA Corporation

10.1.1 NVIDIA Corporation Details

10.1.2 NVIDIA Corporation Major Business

10.1.3 NVIDIA Corporation Grasp Policy Model Product and Services

10.1.4 NVIDIA Corporation Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.1.5 NVIDIA Corporation Recent Developments/Updates

10.1.6 NVIDIA Corporation Competitive Strengths & Weaknesses

10.2 Intrinsic Innovation LLC

10.2.1 Intrinsic Innovation LLC Details

10.2.2 Intrinsic Innovation LLC Major Business

10.2.3 Intrinsic Innovation LLC Grasp Policy Model Product and Services

10.2.4 Intrinsic Innovation LLC Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.2.5 Intrinsic Innovation LLC Recent Developments/Updates

10.2.6 Intrinsic Innovation LLC Competitive Strengths & Weaknesses

10.3 Covariant AI, Inc.

10.3.1 Covariant AI, Inc. Details

10.3.2 Covariant AI, Inc. Major Business

10.3.3 Covariant AI, Inc. Grasp Policy Model Product and Services

10.3.4 Covariant AI, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.3.5 Covariant AI, Inc. Recent Developments/Updates

10.3.6 Covariant AI, Inc. Competitive Strengths & Weaknesses

10.4 OSARO, Inc.

10.4.1 OSARO, Inc. Details

10.4.2 OSARO, Inc. Major Business

10.4.3 OSARO, Inc. Grasp Policy Model Product and Services

10.4.4 OSARO, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share

(2021-2026)

10.4.5 OSARO, Inc. Recent Developments/Updates

10.4.6 OSARO, Inc. Competitive Strengths & Weaknesses

10.5 Plus One Robotics, Inc.

10.5.1 Plus One Robotics, Inc. Details

10.5.2 Plus One Robotics, Inc. Major Business

10.5.3 Plus One Robotics, Inc. Grasp Policy Model Product and Services

10.5.4 Plus One Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and

Market Share (2021-2026)

10.5.5 Plus One Robotics, Inc. Recent Developments/Updates

10.5.6 Plus One Robotics, Inc. Competitive Strengths & Weaknesses

10.6 RightHand Robotics, Inc.

10.6.1 RightHand Robotics, Inc. Details

10.6.2 RightHand Robotics, Inc. Major Business

10.6.3 RightHand Robotics, Inc. Grasp Policy Model Product and Services

10.6.4 RightHand Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and

Market Share (2021-2026)

10.6.5 RightHand Robotics, Inc. Recent Developments/Updates

10.6.6 RightHand Robotics, Inc. Competitive Strengths & Weaknesses

10.7 Mujin, Inc.

10.7.1 Mujin, Inc. Details

10.7.2 Mujin, Inc. Major Business

10.7.3 Mujin, Inc. Grasp Policy Model Product and Services

10.7.4 Mujin, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share

(2021-2026)

10.7.5 Mujin, Inc. Recent Developments/Updates

10.7.6 Mujin, Inc. Competitive Strengths & Weaknesses

10.8 KUKA AG

10.8.1 KUKA AG Details

10.8.2 KUKA AG Major Business

10.8.3 KUKA AG Grasp Policy Model Product and Services

10.8.4 KUKA AG Grasp Policy Model Revenue, Gross Margin and Market Share

(2021-2026)

10.8.5 KUKA AG Recent Developments/Updates

10.8.6 KUKA AG Competitive Strengths & Weaknesses

10.9 Festo SE & Co. KG

10.9.1 Festo SE & Co. KG Details

10.9.2 Festo SE & Co. KG Major Business

10.9.3 Festo SE & Co. KG Grasp Policy Model Product and Services

10.9.4 Festo SE & Co. KG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.9.5 Festo SE & Co. KG Recent Developments/Updates

10.9.6 Festo SE & Co. KG Competitive Strengths & Weaknesses

10.10 SCHUNK SE & Co. KG

10.10.1 SCHUNK SE & Co. KG Details

10.10.2 SCHUNK SE & Co. KG Major Business

10.10.3 SCHUNK SE & Co. KG Grasp Policy Model Product and Services

10.10.4 SCHUNK SE & Co. KG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.10.5 SCHUNK SE & Co. KG Recent Developments/Updates

10.10.6 SCHUNK SE & Co. KG Competitive Strengths & Weaknesses

10.11 Basler AG

10.11.1 Basler AG Details

10.11.2 Basler AG Major Business

10.11.3 Basler AG Grasp Policy Model Product and Services

10.11.4 Basler AG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.11.5 Basler AG Recent Developments/Updates

10.11.6 Basler AG Competitive Strengths & Weaknesses

10.12 Roboception GmbH

10.12.1 Roboception GmbH Details

10.12.2 Roboception GmbH Major Business

10.12.3 Roboception GmbH Grasp Policy Model Product and Services

10.12.4 Roboception GmbH Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.12.5 Roboception GmbH Recent Developments/Updates

10.12.6 Roboception GmbH Competitive Strengths & Weaknesses

10.13 Apera AI Inc.

10.13.1 Apera AI Inc. Details

10.13.2 Apera AI Inc. Major Business

10.13.3 Apera AI Inc. Grasp Policy Model Product and Services

10.13.4 Apera AI Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)

10.13.5 Apera AI Inc. Recent Developments/Updates

10.13.6 Apera AI Inc. Competitive Strengths & Weaknesses

10.14 Realtime Robotics, Inc.

10.14.1 Realtime Robotics, Inc. Details

10.14.2 Realtime Robotics, Inc. Major Business

- 10.14.3 Realtime Robotics, Inc. Grasp Policy Model Product and Services
- 10.14.4 Realtime Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)
- 10.14.5 Realtime Robotics, Inc. Recent Developments/Updates
- 10.14.6 Realtime Robotics, Inc. Competitive Strengths & Weaknesses
- 10.15 Mech-Mind Robotics
 - 10.15.1 Mech-Mind Robotics Details
 - 10.15.2 Mech-Mind Robotics Major Business
 - 10.15.3 Mech-Mind Robotics Grasp Policy Model Product and Services
 - 10.15.4 Mech-Mind Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)
 - 10.15.5 Mech-Mind Robotics Recent Developments/Updates
 - 10.15.6 Mech-Mind Robotics Competitive Strengths & Weaknesses
- 10.16 XYZ Robotics
 - 10.16.1 XYZ Robotics Details
 - 10.16.2 XYZ Robotics Major Business
 - 10.16.3 XYZ Robotics Grasp Policy Model Product and Services
 - 10.16.4 XYZ Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)
 - 10.16.5 XYZ Robotics Recent Developments/Updates
 - 10.16.6 XYZ Robotics Competitive Strengths & Weaknesses
- 10.17 Dobot Robotics
 - 10.17.1 Dobot Robotics Details
 - 10.17.2 Dobot Robotics Major Business
 - 10.17.3 Dobot Robotics Grasp Policy Model Product and Services
 - 10.17.4 Dobot Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026)
 - 10.17.5 Dobot Robotics Recent Developments/Updates
 - 10.17.6 Dobot Robotics Competitive Strengths & Weaknesses

11 INDUSTRY CHAIN ANALYSIS

- 11.1 Grasp Policy Model Industry Chain
- 11.2 Grasp Policy Model Upstream Analysis
- 11.3 Grasp Policy Model Midstream Analysis
- 11.4 Grasp Policy Model Downstream Analysis

12 RESEARCH FINDINGS AND CONCLUSION

13 APPENDIX

13.1 Methodology

13.2 Research Process and Data Source

13.3 Disclaimer

List Of Tables

LIST OF TABLES

- Table 1. World Grasp Policy Model Revenue by Region (2021, 2025 and 2032) & (USD Million), (by Headquarter Location)
- Table 2. World Grasp Policy Model Revenue by Region (2021-2026) & (USD Million), (by Headquarter Location)
- Table 3. World Grasp Policy Model Revenue by Region (2027-2032) & (USD Million), (by Headquarter Location)
- Table 4. World Grasp Policy Model Revenue Market Share by Region (2021-2026), (by Headquarter Location)
- Table 5. World Grasp Policy Model Revenue Market Share by Region (2027-2032), (by Headquarter Location)
- Table 6. Major Market Trends
- Table 7. World Grasp Policy Model Consumption Value Growth Rate Forecast by Region (2021 & 2025 & 2032) & (USD Million)
- Table 8. World Grasp Policy Model Consumption Value by Region (2021-2026) & (USD Million)
- Table 9. World Grasp Policy Model Consumption Value Forecast by Region (2027-2032) & (USD Million)
- Table 10. World Grasp Policy Model Revenue by Player (2021-2026) & (USD Million)
- Table 11. Revenue Market Share of Key Grasp Policy Model Players in 2025
- Table 12. World Grasp Policy Model Industry Rank of Major Player, Based on Revenue in 2025
- Table 13. Global Grasp Policy Model Company Evaluation Quadrant
- Table 14. Head Office of Key Grasp Policy Model Players
- Table 15. Grasp Policy Model Market: Company Product Type Footprint
- Table 16. Grasp Policy Model Market: Company Product Application Footprint
- Table 17. Grasp Policy Model Mergers & Acquisitions Activity
- Table 18. United States VS China Grasp Policy Model Revenue Comparison, (2021 & 2025 & 2032) & (USD Million)
- Table 19. United States VS China Grasp Policy Model Consumption Value Comparison, (2021 & 2025 & 2032) & (USD Million)
- Table 20. United States Based Grasp Policy Model Companies, Headquarters (States, Country)
- Table 21. United States Based Companies Grasp Policy Model Revenue, (2021-2026) & (USD Million)
- Table 22. United States Based Companies Grasp Policy Model Revenue Market Share

(2021-2026)

Table 23. China Based Grasp Policy Model Companies, Headquarters (Province, Country)

Table 24. China Based Companies Grasp Policy Model Revenue, (2021-2026) & (USD Million)

Table 25. China Based Companies Grasp Policy Model Revenue Market Share (2021-2026)

Table 26. Rest of World Based Grasp Policy Model Companies, Headquarters (Province, Country)

Table 27. Rest of World Based Companies Grasp Policy Model Revenue (2021-2026) & (USD Million)

Table 28. Rest of World Based Companies Grasp Policy Model Revenue Market Share (2021-2026)

Table 29. World Grasp Policy Model Market Size by Perception Input, (USD Million), 2021 & 2025 & 2032

Table 30. World Grasp Policy Model Market Size Value by Perception Input (2021-2026) & (USD Million)

Table 31. World Grasp Policy Model Market Size by Perception Input (2027-2032) & (USD Million)

Table 32. World Grasp Policy Model Market Size by Decision Paradigm, (USD Million), 2021 & 2025 & 2032

Table 33. World Grasp Policy Model Market Size Value by Decision Paradigm (2021-2026) & (USD Million)

Table 34. World Grasp Policy Model Market Size by Decision Paradigm (2027-2032) & (USD Million)

Table 35. World Grasp Policy Model Market Size by Control Loop, (USD Million), 2021 & 2025 & 2032

Table 36. World Grasp Policy Model Market Size Value by Control Loop (2021-2026) & (USD Million)

Table 37. World Grasp Policy Model Market Size by Control Loop (2027-2032) & (USD Million)

Table 38. World Grasp Policy Model Market Size by Target Object State, (USD Million), 2021 & 2025 & 2032

Table 39. World Grasp Policy Model Market Size Value by Target Object State (2021-2026) & (USD Million)

Table 40. World Grasp Policy Model Market Size by Target Object State (2027-2032) & (USD Million)

Table 41. World Grasp Policy Model Market Size by Application, (USD Million), 2021 & 2025 & 2032

Table 42. World Grasp Policy Model Market Size by Application (2021-2026) & (USD Million)

Table 43. World Grasp Policy Model Market Size by Application (2027-2032) & (USD Million)

Table 44. NVIDIA Corporation Basic Information, Manufacturing Base and Competitors

Table 45. NVIDIA Corporation Major Business

Table 46. NVIDIA Corporation Grasp Policy Model Product and Services

Table 47. NVIDIA Corporation Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)

Table 48. NVIDIA Corporation Recent Developments/Updates

Table 49. NVIDIA Corporation Competitive Strengths & Weaknesses

Table 50. Intrinsic Innovation LLC Basic Information, Manufacturing Base and Competitors

Table 51. Intrinsic Innovation LLC Major Business

Table 52. Intrinsic Innovation LLC Grasp Policy Model Product and Services

Table 53. Intrinsic Innovation LLC Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)

Table 54. Intrinsic Innovation LLC Recent Developments/Updates

Table 55. Intrinsic Innovation LLC Competitive Strengths & Weaknesses

Table 56. Covariant AI, Inc. Basic Information, Manufacturing Base and Competitors

Table 57. Covariant AI, Inc. Major Business

Table 58. Covariant AI, Inc. Grasp Policy Model Product and Services

Table 59. Covariant AI, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)

Table 60. Covariant AI, Inc. Recent Developments/Updates

Table 61. Covariant AI, Inc. Competitive Strengths & Weaknesses

Table 62. OSARO, Inc. Basic Information, Manufacturing Base and Competitors

Table 63. OSARO, Inc. Major Business

Table 64. OSARO, Inc. Grasp Policy Model Product and Services

Table 65. OSARO, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)

Table 66. OSARO, Inc. Recent Developments/Updates

Table 67. OSARO, Inc. Competitive Strengths & Weaknesses

Table 68. Plus One Robotics, Inc. Basic Information, Manufacturing Base and Competitors

Table 69. Plus One Robotics, Inc. Major Business

Table 70. Plus One Robotics, Inc. Grasp Policy Model Product and Services

Table 71. Plus One Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)

Table 72. Plus One Robotics, Inc. Recent Developments/Updates
Table 73. Plus One Robotics, Inc. Competitive Strengths & Weaknesses
Table 74. RightHand Robotics, Inc. Basic Information, Manufacturing Base and Competitors
Table 75. RightHand Robotics, Inc. Major Business
Table 76. RightHand Robotics, Inc. Grasp Policy Model Product and Services
Table 77. RightHand Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 78. RightHand Robotics, Inc. Recent Developments/Updates
Table 79. RightHand Robotics, Inc. Competitive Strengths & Weaknesses
Table 80. Mujin, Inc. Basic Information, Manufacturing Base and Competitors
Table 81. Mujin, Inc. Major Business
Table 82. Mujin, Inc. Grasp Policy Model Product and Services
Table 83. Mujin, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 84. Mujin, Inc. Recent Developments/Updates
Table 85. Mujin, Inc. Competitive Strengths & Weaknesses
Table 86. KUKA AG Basic Information, Manufacturing Base and Competitors
Table 87. KUKA AG Major Business
Table 88. KUKA AG Grasp Policy Model Product and Services
Table 89. KUKA AG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 90. KUKA AG Recent Developments/Updates
Table 91. KUKA AG Competitive Strengths & Weaknesses
Table 92. Festo SE & Co. KG Basic Information, Manufacturing Base and Competitors
Table 93. Festo SE & Co. KG Major Business
Table 94. Festo SE & Co. KG Grasp Policy Model Product and Services
Table 95. Festo SE & Co. KG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 96. Festo SE & Co. KG Recent Developments/Updates
Table 97. Festo SE & Co. KG Competitive Strengths & Weaknesses
Table 98. SCHUNK SE & Co. KG Basic Information, Manufacturing Base and Competitors
Table 99. SCHUNK SE & Co. KG Major Business
Table 100. SCHUNK SE & Co. KG Grasp Policy Model Product and Services
Table 101. SCHUNK SE & Co. KG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 102. SCHUNK SE & Co. KG Recent Developments/Updates
Table 103. SCHUNK SE & Co. KG Competitive Strengths & Weaknesses

Table 104. Basler AG Basic Information, Manufacturing Base and Competitors
Table 105. Basler AG Major Business
Table 106. Basler AG Grasp Policy Model Product and Services
Table 107. Basler AG Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 108. Basler AG Recent Developments/Updates
Table 109. Basler AG Competitive Strengths & Weaknesses
Table 110. Roboception GmbH Basic Information, Manufacturing Base and Competitors
Table 111. Roboception GmbH Major Business
Table 112. Roboception GmbH Grasp Policy Model Product and Services
Table 113. Roboception GmbH Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 114. Roboception GmbH Recent Developments/Updates
Table 115. Roboception GmbH Competitive Strengths & Weaknesses
Table 116. Apera AI Inc. Basic Information, Manufacturing Base and Competitors
Table 117. Apera AI Inc. Major Business
Table 118. Apera AI Inc. Grasp Policy Model Product and Services
Table 119. Apera AI Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 120. Apera AI Inc. Recent Developments/Updates
Table 121. Apera AI Inc. Competitive Strengths & Weaknesses
Table 122. Realtime Robotics, Inc. Basic Information, Manufacturing Base and Competitors
Table 123. Realtime Robotics, Inc. Major Business
Table 124. Realtime Robotics, Inc. Grasp Policy Model Product and Services
Table 125. Realtime Robotics, Inc. Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 126. Realtime Robotics, Inc. Recent Developments/Updates
Table 127. Realtime Robotics, Inc. Competitive Strengths & Weaknesses
Table 128. Mech-Mind Robotics Basic Information, Manufacturing Base and Competitors
Table 129. Mech-Mind Robotics Major Business
Table 130. Mech-Mind Robotics Grasp Policy Model Product and Services
Table 131. Mech-Mind Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 132. Mech-Mind Robotics Recent Developments/Updates
Table 133. Mech-Mind Robotics Competitive Strengths & Weaknesses
Table 134. XYZ Robotics Basic Information, Manufacturing Base and Competitors
Table 135. XYZ Robotics Major Business

Table 136. XYZ Robotics Grasp Policy Model Product and Services
Table 137. XYZ Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 138. XYZ Robotics Recent Developments/Updates
Table 139. XYZ Robotics Competitive Strengths & Weaknesses
Table 140. Dobot Robotics Basic Information, Manufacturing Base and Competitors
Table 141. Dobot Robotics Major Business
Table 142. Dobot Robotics Grasp Policy Model Product and Services
Table 143. Dobot Robotics Grasp Policy Model Revenue, Gross Margin and Market Share (2021-2026) & (USD Million)
Table 144. Dobot Robotics Recent Developments/Updates
Table 145. Dobot Robotics Competitive Strengths & Weaknesses
Table 146. Global Key Players of Grasp Policy Model Upstream (Raw Materials)
Table 147. Global Grasp Policy Model Typical Customers

List Of Figures

LIST OF FIGURES

Figure 1. Grasp Policy Model Picture

Figure 2. World Grasp Policy Model Total Revenue: 2021 & 2025 & 2032, (USD Million)

Figure 3. World Grasp Policy Model Total Revenue (2021-2032) & (USD Million)

Figure 4. World Grasp Policy Model Revenue by Region (2021, 2025 and 2032) & (USD Million), (by Headquarter Location)

Figure 5. World Grasp Policy Model Revenue Market Share by Region (2021-2032), (by Headquarter Location)

Figure 6. United States Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 7. China Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 8. Europe Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 9. Japan Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 10. South Korea Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 11. ASEAN Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 12. India Based Company Grasp Policy Model Revenue (2021-2032) & (USD Million)

Figure 13. Grasp Policy Model Market Drivers

Figure 14. Factors Affecting Demand

Figure 15. World Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 16. World Grasp Policy Model Consumption Value Market Share by Region (2021-2032)

Figure 17. United States Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 18. China Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 19. Europe Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 20. Japan Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 21. South Korea Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 22. ASEAN Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 23. India Grasp Policy Model Consumption Value (2021-2032) & (USD Million)

Figure 24. Producer Shipments of Grasp Policy Model by Player Revenue (\$MM) and Market Share (%): 2025

Figure 25. Global Four-firm Concentration Ratios (CR4) for Grasp Policy Model Markets in 2025

Figure 26. Global Four-firm Concentration Ratios (CR8) for Grasp Policy Model Markets in 2025

Figure 27. United States VS China: Grasp Policy Model Revenue Market Share Comparison (2021 & 2025 & 2032)

Figure 28. United States VS China: Grasp Policy Model Consumption Value Market Share Comparison (2021 & 2025 & 2032)

Figure 29. World Grasp Policy Model Market Size by Perception Input, (USD Million), 2021 & 2025 & 2032

Figure 30. World Grasp Policy Model Market Size Market Share by Perception Input in 2025

Figure 31. 2D Vision Model

Figure 32. 3D Point Cloud Model

Figure 33. Multimodal Vision Model

Figure 34. Tactile Force-Control Model

Figure 35. Other

Figure 36. World Grasp Policy Model Market Size Market Share by Perception Input (2021-2032)

Figure 37. World Grasp Policy Model Market Size by Decision Paradigm, (USD Million), 2021 & 2025 & 2032

Figure 38. World Grasp Policy Model Market Size Market Share by Decision Paradigm in 2025

Figure 39. Rule-Based Geometric Model

Figure 40. Supervised Learning Model

Figure 41. Reinforcement Learning Model

Figure 42. Imitation Learning Model

Figure 43. Generative Diffusion Model

Figure 44. Foundation Model

Figure 45. World Grasp Policy Model Market Size Market Share by Decision Paradigm (2021-2032)

Figure 46. World Grasp Policy Model Market Size by Control Loop, (USD Million), 2021 & 2025 & 2032

Figure 47. World Grasp Policy Model Market Size Market Share by Control Loop in 2025

Figure 48. Open-Loop Grasping Model

Figure 49. Visual Closed-Loop Model

Figure 50. Force-Sensing Closed-Loop Model

Figure 51. Vision-Tactile Fusion Closed-Loop Model

Figure 52. World Grasp Policy Model Market Size Market Share by Control Loop
(2021-2032)

Figure 53. World Grasp Policy Model Market Size by Target Object State, (USD Million),
2021 & 2025 & 2032

Figure 54. World Grasp Policy Model Market Size Market Share by Target Object State
in 2025

Figure 55. Regular Rigid Object Model

Figure 56. Cluttered Stacked Object Model

Figure 57. Transparent and Reflective Object Model

Figure 58. Flexible Packaging Object Model

Figure 59. Entangled Wire Harness Object Model

Figure 60. Other

Figure 61. World Grasp Policy Model Market Size Market Share by Target Object State
(2021-2032)

Figure 62. World Grasp Policy Model Market Size by Application, (USD Million), 2021 &
2025 & 2032

Figure 63. World Grasp Policy Model Market Size Market Share by Application in 2025

Figure 64. Item Piece Picking

Figure 65. Industrial Bin Picking

Figure 66. Carton Depalletizing

Figure 67. Parcel Induction

Figure 68. Assembly Feeding

Figure 69. Service Object Retrieval

Figure 70. Other

Figure 71. World Grasp Policy Model Market Size Market Share by Application
(2021-2032)

Figure 72. Grasp Policy Model Industrial Chain

Figure 73. Methodology

Figure 74. Research Process and Data Source

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