

Review of: "FastGrasp: Efficient Grasp Synthesis with Diffusion"

Guanjun Bao¹

¹ Zhejiang University of Technology, China

Potential competing interests: No potential competing interests to declare.

This paper developed a fast grasp planning method with a diffusion model and physical constraints, which was verified by simulation and comparison with state-of-the-art algorithms. It was illustrated that the method was faster than other methods. To further improve the document, I suggest that:

1. It seems that all the simulated grasping plans were generated by the trained model with similar datasets. Could you give some theory or simulated results that the proposed method can generalize to unfamiliar scenarios?
2. Although it might be difficult, physical experiments are still expected to prove the work.