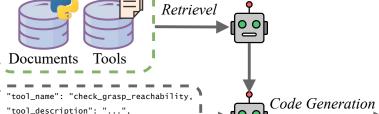
ToolGen Agents



def safety_margin(self, actor, required_margin=0.03): return float(nearest_gap - required_margin) def check_grasp_reachability(.....) : return ee_pos - handle_pos

Tool Code

Proposed

"tool_name": "safety_margin, "tool_description": "...",

Tool Proposal

_ 00 Context from Proposal Stage

Task Code from TaskGen Agent