Input: Task prompt with requirements and constraints

User

Train a visuomotor policy for bimanual Aloha-AgileX that can place a cup onto a plate with over 50% success under object pose randomization and tabletop height randomization exceeding 5 cm, using head and wrist cameras as visual input, trained from at most 200 collected demonstrations.

AutoManipLab

Iterative Development

Planning Agent

Tools

Plan

CLI Coding Agent

Skills Library

Code Execute

RoboTwin

ManiSkill

Simulation Engines

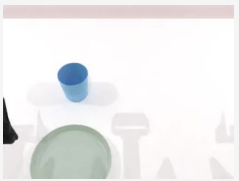
Data Collection

Training

Evaluation

...

Output: Deliverable model that meets the user requirements



Place Cup on Plate.

Success Rate: 0.53

[Δx, Δθ, ΔGrip] = ...