

Poster Placeholder

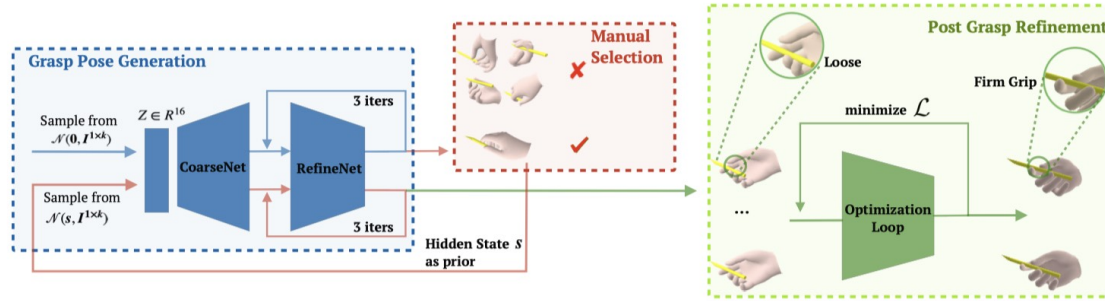


Fig. 2. The Hand manipulation sequence generation pipeline consists of three components: grasp pose generation, pose selection, and pose refinement, highlighted in blue, red, and green, respectively.

2.2 Hand-object manipulation sequence generation

There are two critical differences between the surgical tool and everyday object grasping: surgical tools require to be held in specific poses. Moreover, a surgeon would hold firmly and steadily with a particular pose for some time span during surgeries.

To address this issue, we generate each instrument manipulation sequence by firstly modeling the key poses that are surgically plausible, and then interpo-