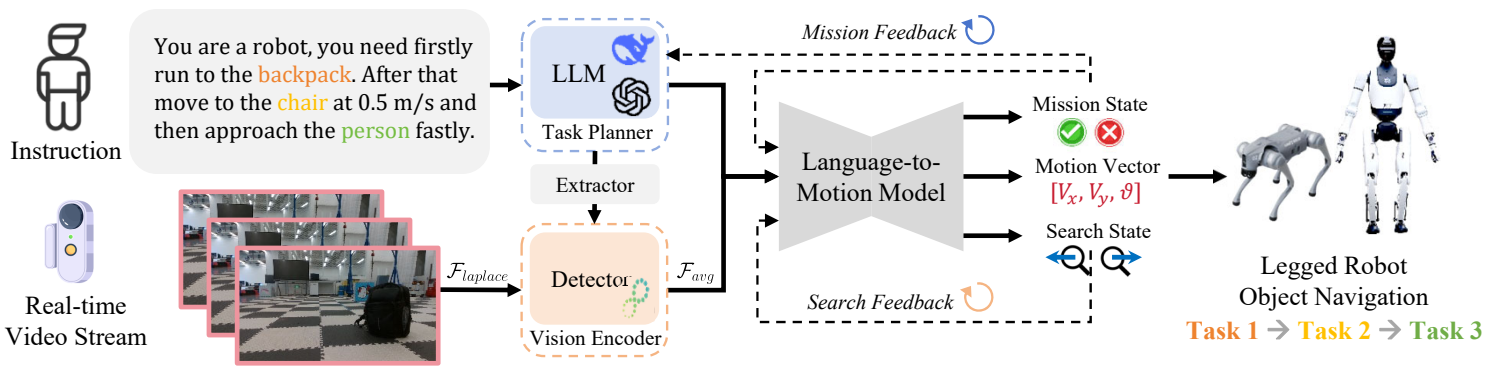

LLM-based Task Planner

Prompts:

Your task is to decompose the input instruction into subtasks and number them as Task *i* with specific format...
When the robot returns `succuss`, send the next Task...

LLM Response:

Task 1: Run to the chair at 0.4m/s
Task 2: Move to the chair at 0.5m/s
Task 3: Approach to the person at 0.8m/s
...

Interact

User:

Success

LLM Response:

Task Success

Language-to-Motion Model