

Input

Pick the bottle and pour in the glass



Language Model

DMP Library

Symbolic Task Plan

1. Reach [Bottle]
2. Grasp [Bottle]
3. Pick-Up [Bottle]
4. Reach [BOX]
5. Place-Down [BOX]
6. Release [Bottle]
7. Retract

Environment Analyzer



* There are 10 different objects on which we have worked

Desired
Object
Found

True

False

END

Robot Execution
Model

Each sub-action is trained using the DMP model by manually guiding the robot manipulator, which serves as the basis for the DMP library.



Execution of Sub-actions

