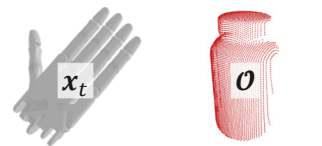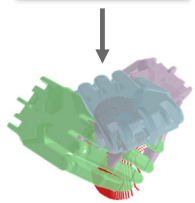**Arm-Agnostic** Grasp Model

Input

Noisy Hand Object Input

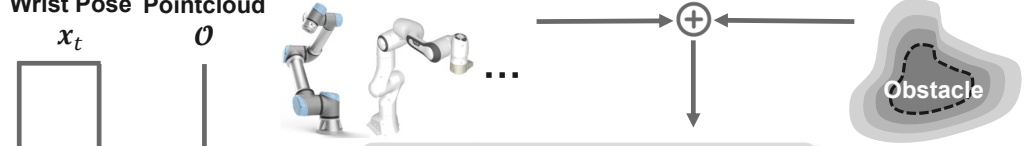x_t $\mathcal{O}$

Diffuser $\times T$

Grasp Pose

Arm-Aware Dexterous Grasp Generation
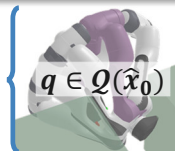
Input **Output**

Noisy Wrist Pose x_t Object Pointcloud $\mathcal{O}$ Arm Kinematics Environment SDF

Obstacle

Diffuser $\times T$

Collision Avoidance $f_{\text{colli}}(q)$
Hand Reachability $f_{\text{reach}}(x, q)$
Joint Proximity $f_{\text{joint}}(q)$

$\times \lambda_{c,t}$
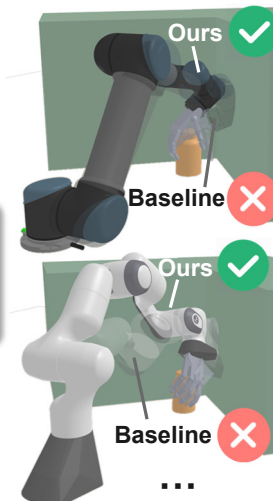
$\nabla g(\hat{x}_0) = \nabla f_x(\hat{x}_0, q^*)$

$\hat{x}_0$

IK Solver

$q \in \mathcal{Q}(\hat{x}_0)$

minimum point of loss q^*

predicted wrist pose $\hat{x}_0$

x_{t-1}^{DDIM} $\nabla g(\hat{x}_0)$

denoised wrist pose x_{t-1}

Ours Baseline

Ours Baseline

feasible arm-hand pose (q^*, x_0)