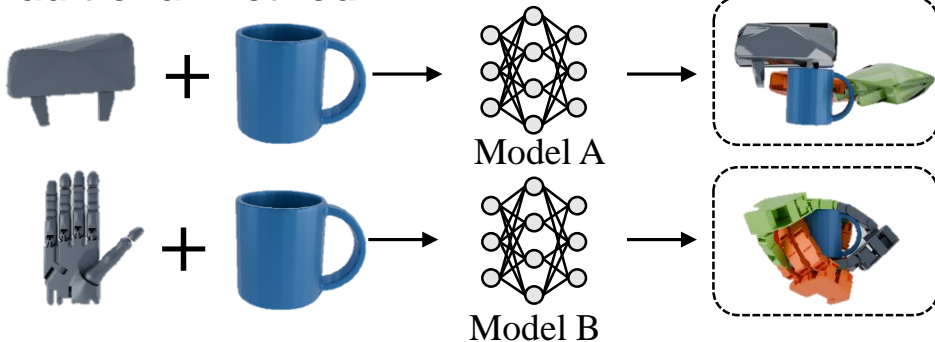


Traditional Method

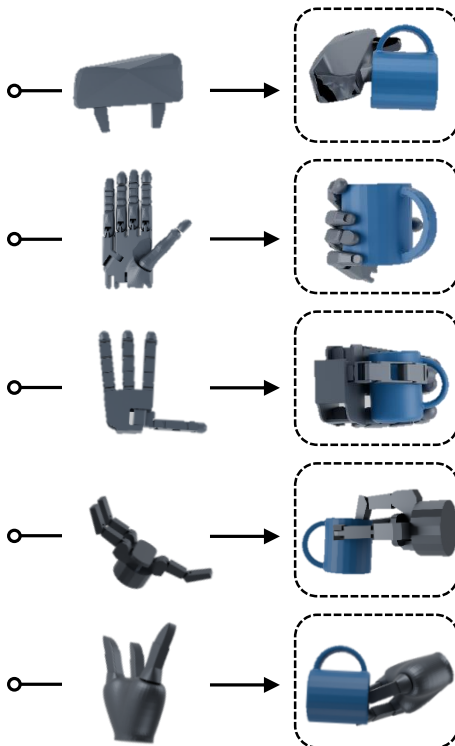


How can the robotics hand grasp the body of mug?



MLLM

Single Model



Multi-GraspLLM