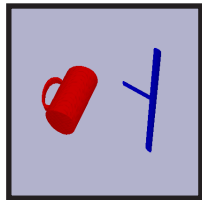
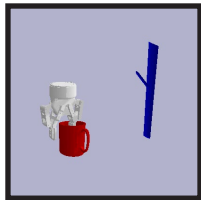


observed point cloud

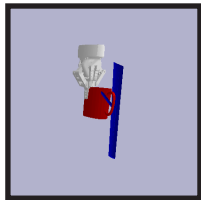
object shape
and pose
inference



inferred scene



grasp demo



placement demo

grasp
prediction

T_{grasp}

placement
prediction

T_{place}