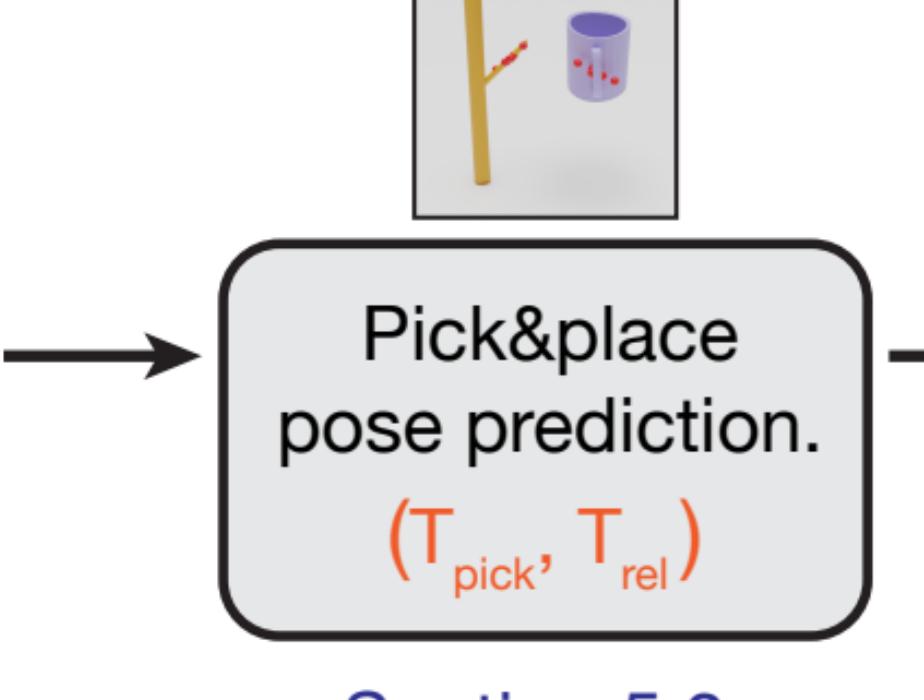


Observed segmented
point cloud.



Pose and shape
inference.
 $((v_1, T_1), (v_2, T_2))$

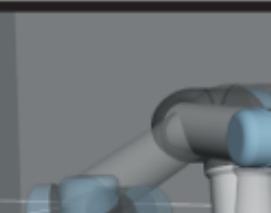
Section 5.2.



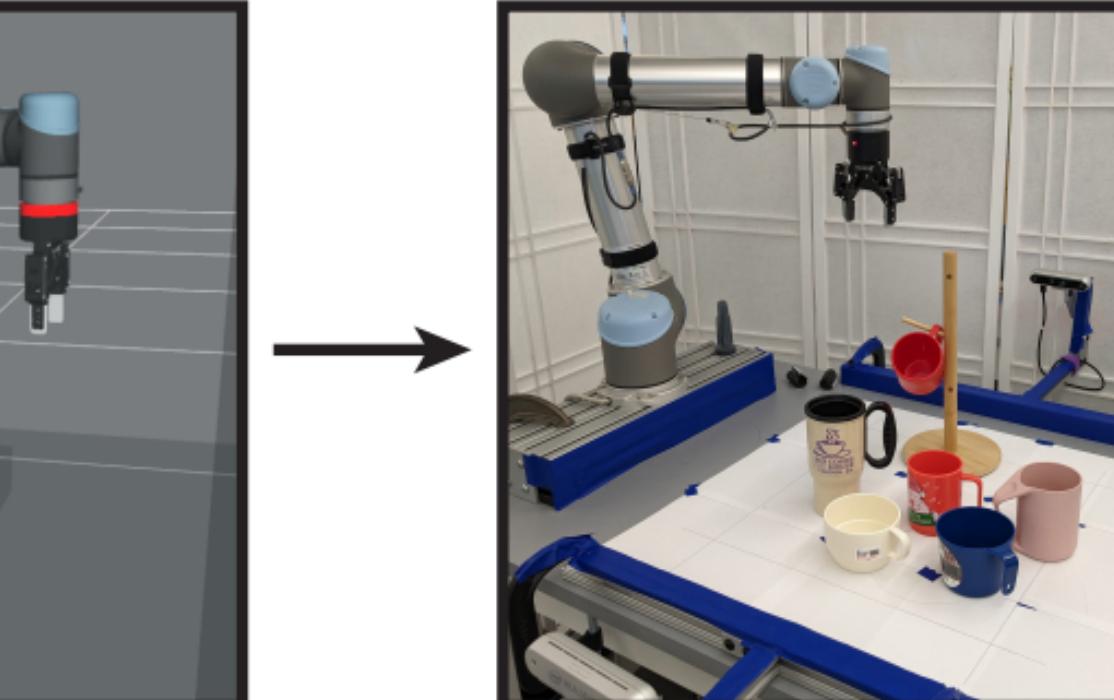
Geometric scene.

Pick&place
pose prediction.
 $(T_{\text{pick}}, T_{\text{rel}})$

Section 5.3.



ROS motion planning.



Execution.