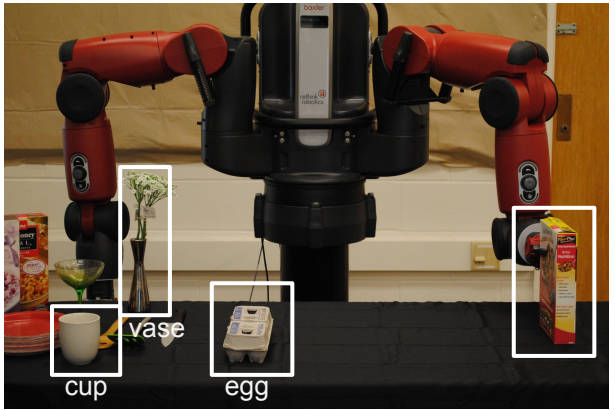
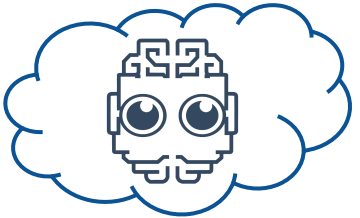
Planning using RoboBrain

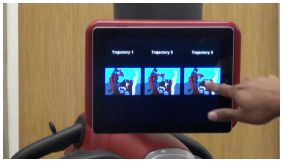


Task: Move the egg carton



$\Theta^*_{new} = f(\Theta^*)$

Co-active Feedback to RoboBrain



User Feedback

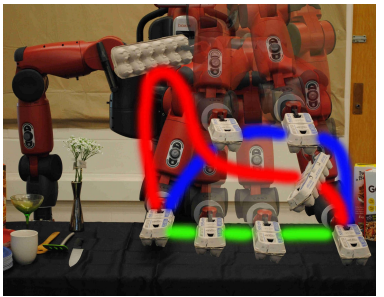
Environment, Objects and Task

Trajectory parameters

Θ^*

PlanIt

$\textit{argmax}\ \Psi(\mathcal{T}|\Theta^*)$



Top three trajectories