



Task-Oriented Part Selection (LLM)



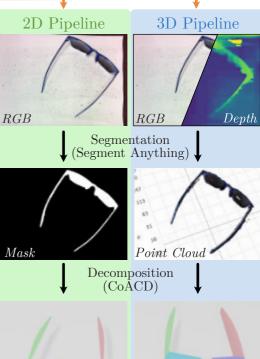
Prompt + Graph + Parts + Prompt = Grasp

$Semantic\ Part\ Identification\ (LLM)$



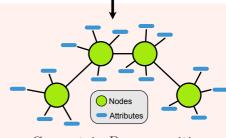
Prompt + Graph = Parts

Our Contribution: Shape Based Inference



2D Decomposition

Heuristic Selection of Decomposition



Geometric Decomposition