

Task: Upright the peg and stack it in the cup.



RoboFAC-7B

<Failure Explanation>

The task failed because the robot arm did not grasp the long block tightly enough during the grasping stage. As a result, when the robot attempted to lift the block, it slipped from the gripper's hold and could not be stacked upright on the red bowl. This indicates a failure in the grasping force applied by the robot arm, which was insufficient for securely holding the object.

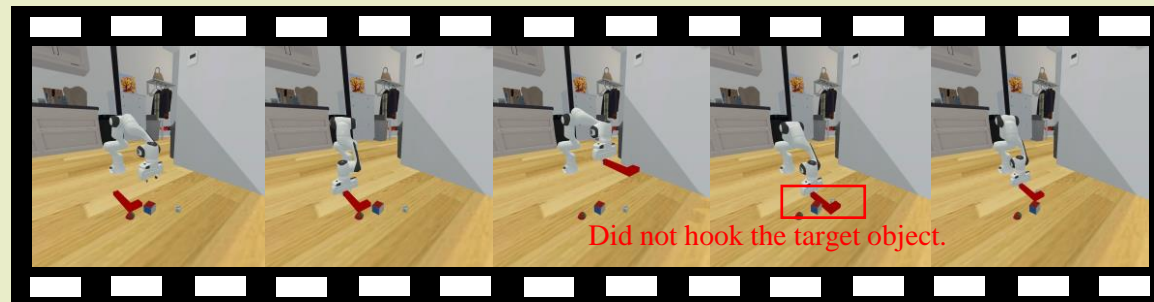


GPT-4o

<Failure Explanation>

The robotic arm failed to complete the task because it did not properly grasp the red cup. The gripper appears to close either too early or at an incorrect angle, resulting in the cup being pushed or knocked over instead of being securely held. Additionally, the arm's positioning relative to the cup seems slightly misaligned, which further contributes to the failure to establish a stable grip. This misalignment and premature gripping action caused the task to fail as the cup was not successfully picked up.

Task: Grasp the L-shaped tool and pull the cube by it.



RoboFAC-7B

<Failure Explanation>

The task failed because the robot arm mistakenly hooked the dice instead of the intended Rubik's cube. This error occurred during the stage where the robot was moving the L-shaped tool behind the strawberry. The presence of multiple objects in close proximity likely led to confusion, resulting in the wrong target object being engaged. As a result, the robot could not complete the task of pulling the strawberry back.



GPT-4o

<Failure Explanation>

The robotic arm failed to complete the task due to improper alignment and grasping of the red L-shaped object. In the video, the arm initially approaches the object correctly but struggles to maintain a stable grip. The arm's movements appear to lack precision, causing the object to slip or be misaligned during manipulation. Additionally, the arm's end-effector does not seem to be optimized for securely holding the L-shaped object, leading to repeated failures in positioning it correctly relative to the other objects in the scene.