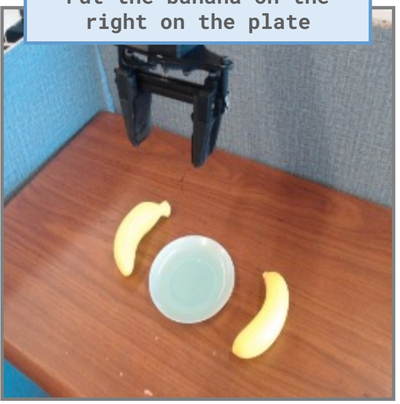
Put the banana on the right on the plate



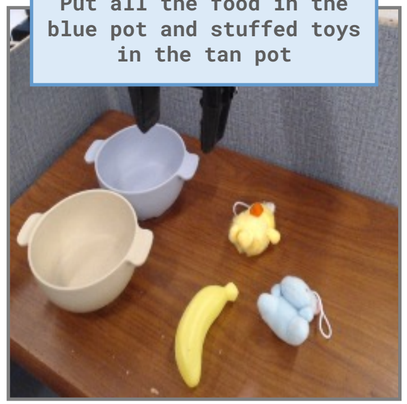
1: The current scene shows the robot arm at the home position with two bananas and a plate on the table. This is a reset to the initial state after the robot mistakenly targeted the left banana instead of the right one.

2: The robot must now correctly target and move toward the banana located on the right side of the plate.

3: A previous attempt using a position-based command with specific tags failed to target the correct banana. Per the instructions, I will now use a different level of abstraction, specifically atomic motion commands, to guide the robot's movement toward the right side of the workspace to ensure it approaches the correct object.

move right and down to the banana on the right

Put all the food in the blue pot and stuffed toys in the tan pot



1: The current scene shows a blue pot, a tan pot, a yellow chick stuffed toy, a blue elephant stuffed toy, and a banana on a wooden table. The robot's gripper is currently positioned open above the blue pot.

2: The robot needs to move towards one of the objects to begin sorting, such as the banana.

3: Since the gripper is currently centered over the blue pot and away from the items, a position-based command is the most efficient way to direct the robot to a specific target. This will allow the object detector to guide the robot directly to the banana for the next phase of the task.

move above [128, 213]

Put all the food in the blue pot and stuffed toys in the tan pot

1: The current scene shows the mushroom stuffed animal remaining on the table while the corn and banana are already in the white bowl. The robot's gripper is positioned directly above the mushroom but failed to secure it during the previous lift attempt.

2: The robot must successfully grasp and lift the mushroom to move it toward the green bowl.

3: Several high-level and combination commands have been attempted without successfully lifting the object. Since the gripper is already well-positioned above the mushroom, a position-based command will help the system re-calculate the exact coordinates for a more precise grasp attempt to ensure the mushroom is actually secured before lifting.

pick up the object at [104, 190]

Put all the food in the blue pot and stuffed toys in the tan pot

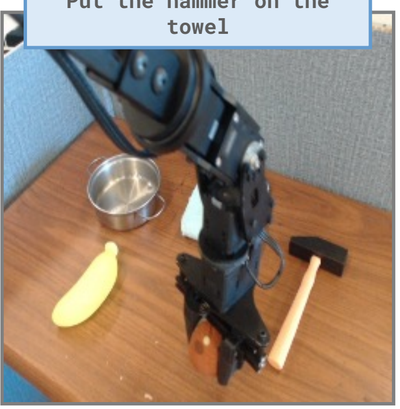
b The robot's gripper is now positioned directly above the banana, having successfully moved from its previous position over the blue pot. The other objects (blue pot, tan pot, yellow chick, and blue elephant) remain in their original locations.

2: The robot must now grasp the banana to begin moving it toward the blue pot.

3: Since the robot is already precisely aligned with the banana, a high-level instruction is the most efficient and reliable way to execute the grasp. The robot has clearly identified the target object.

grasp the banana

Put the hammer on the towel



1: The current scene shows the robot's gripper positioned over a brown and white object at the bottom of the frame, having missed the hammer which is located further to the right. This is a recurring issue where the robot confuses the target object with the vegetable in the foreground.

2: The robot needs to move further to the right to align itself with the hammer handle before attempting another grasp.

3: Previous commands using high-level names, position tags <>, and specific motion directions like "right and down" have consistently resulted in the robot targeting the wrong object. Since the robot is currently too low and targeting the wrong item, an atomic motion command to move strictly right and slightly up will help clear the current object and reposition for the correct target.

move right and up to the hammer handle