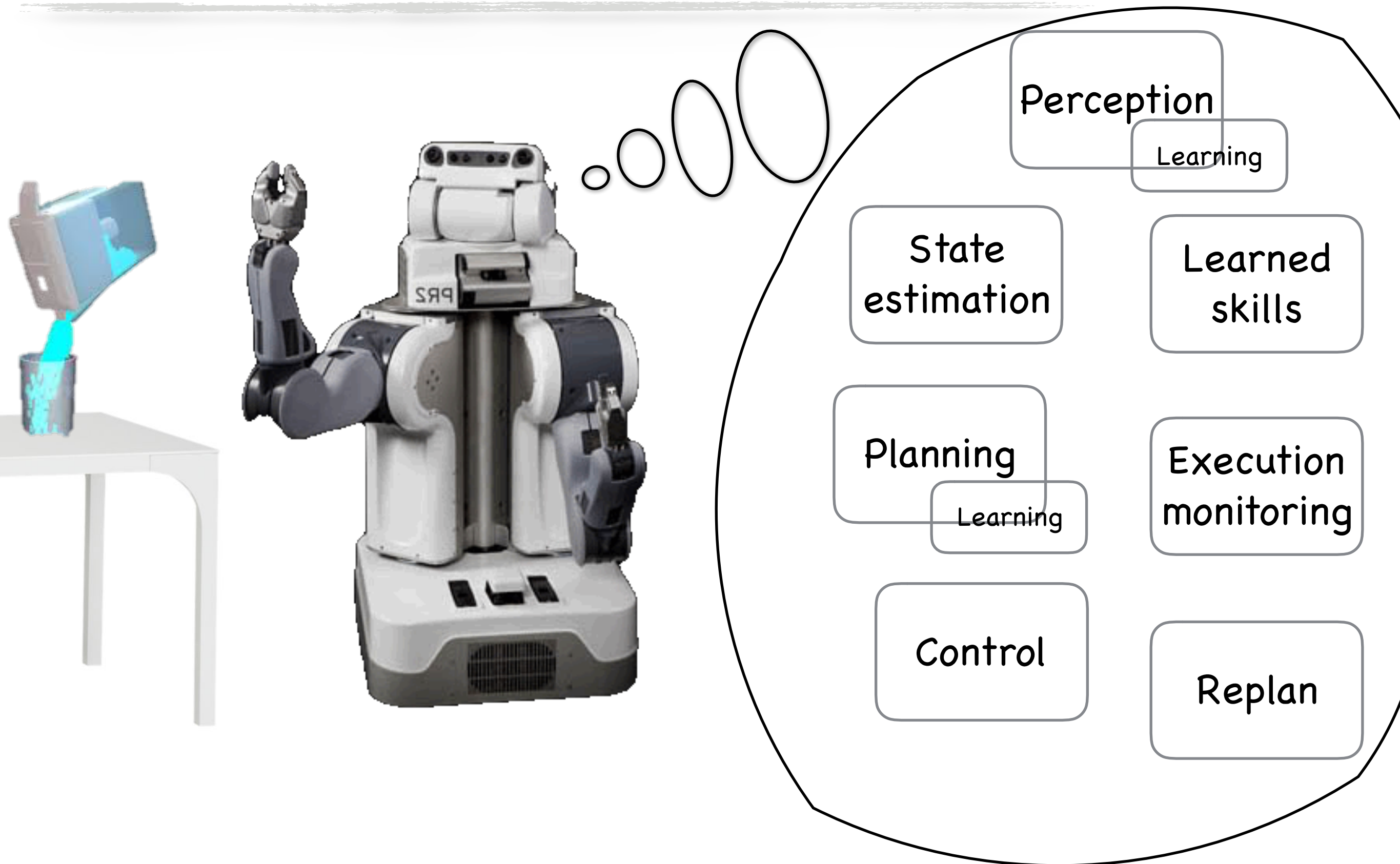
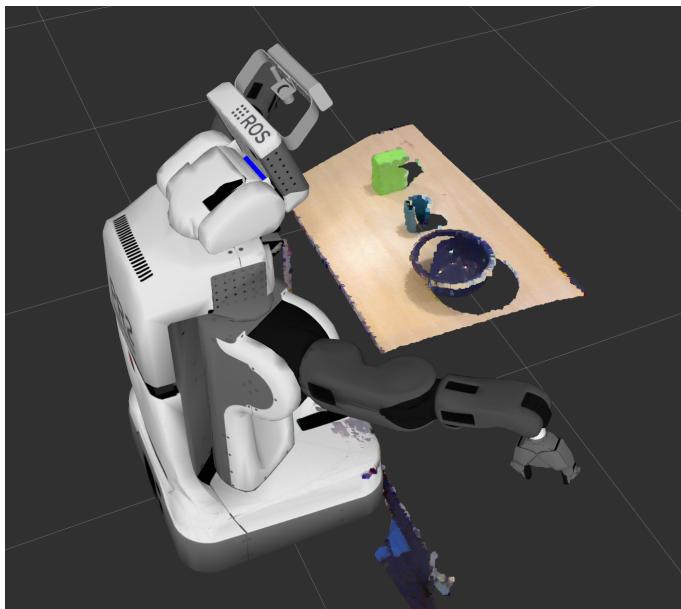


Implementation on the real robot

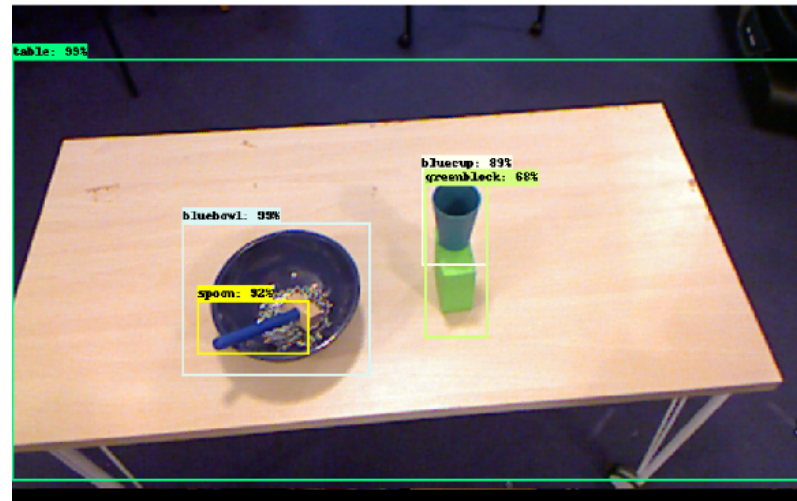


Implementation on the real robot

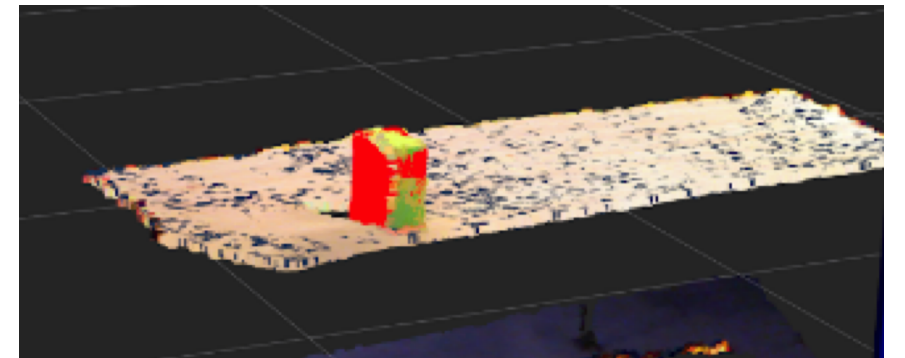
Perception of the world state



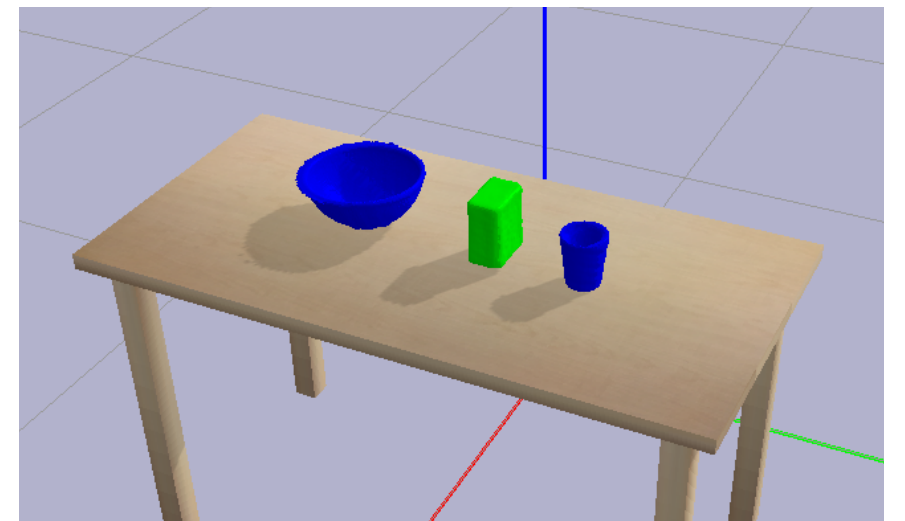
Kinect point cloud



Bounding box detection



3D model alignment



reconstruct state in simulation