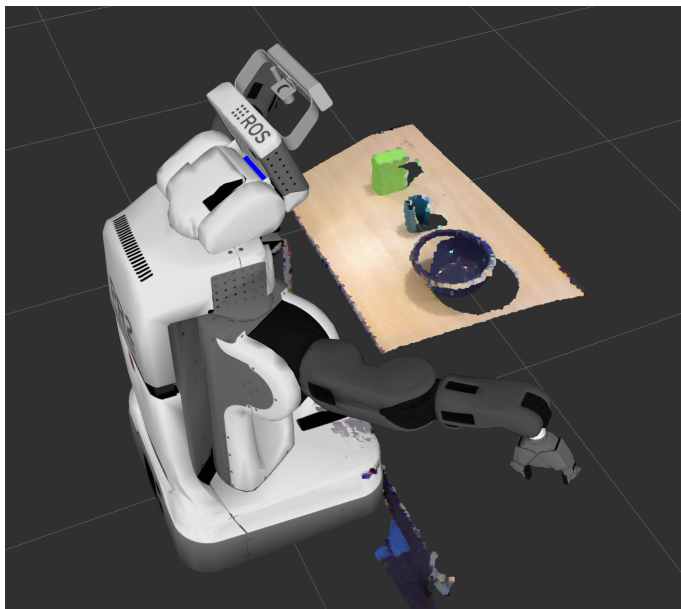
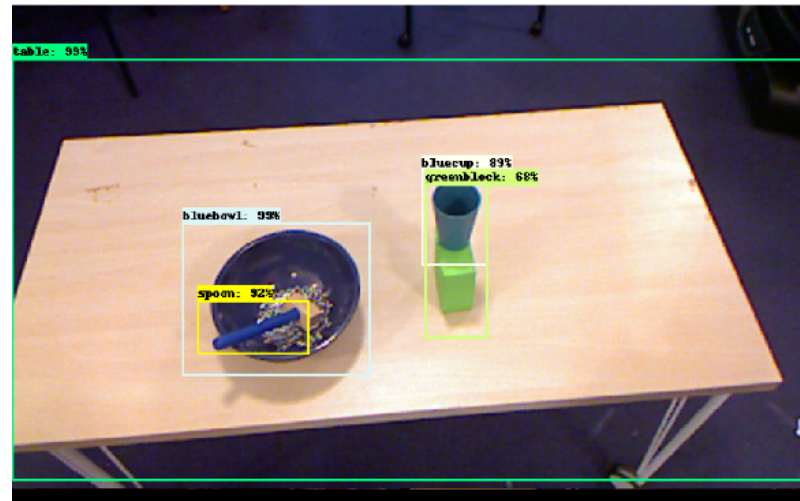


# Implementation on the real robot

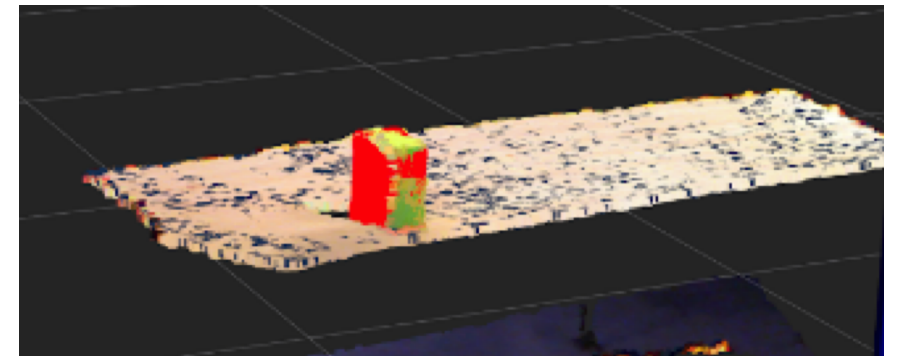
## Perception of the world state



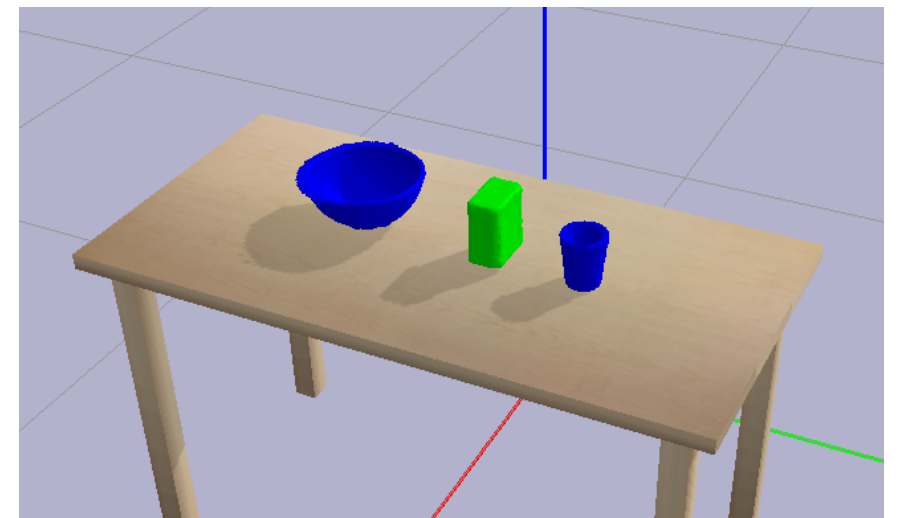
Kinect point cloud



Bounding box detection



3D model alignment



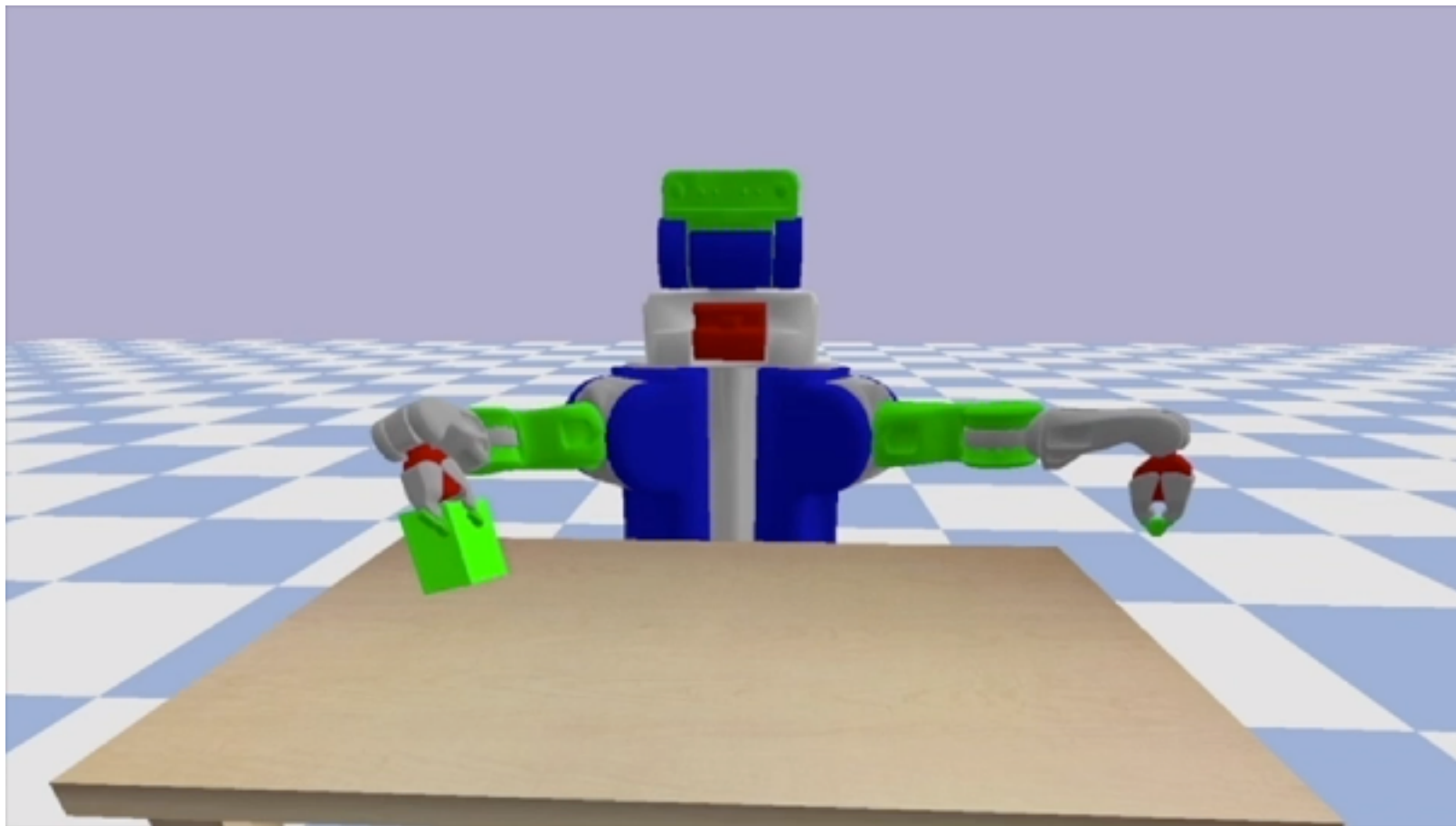
reconstruct state in simulation

# Learning from simulation and real world

Adaptive transfer kernel weights them appropriately

Parameters:

- gripper initial and final y displacement from block
- gripper displacement from block center in z
- gripper opening width
- wrist tilt angle



Objective does not include orientation