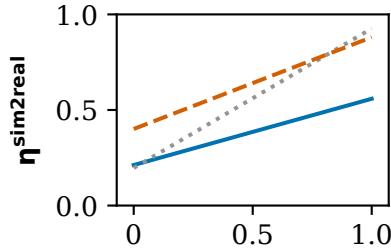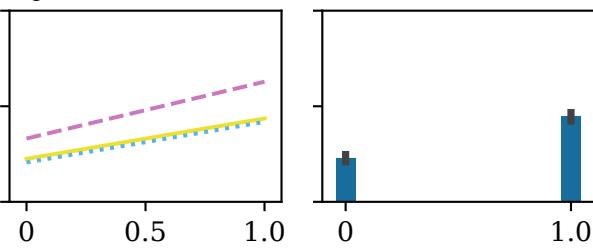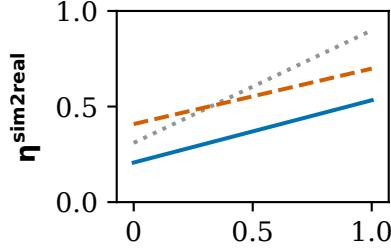Object state DR

Joint states DR

Frictions DR

Mixture DR

Study per robot
— Baxter
⋯ UR5-SIH
-- FR3

Study per method
— DC-NSMBS
⋯ NSMBS
-- ME-scs

One robot in details
— Baxter