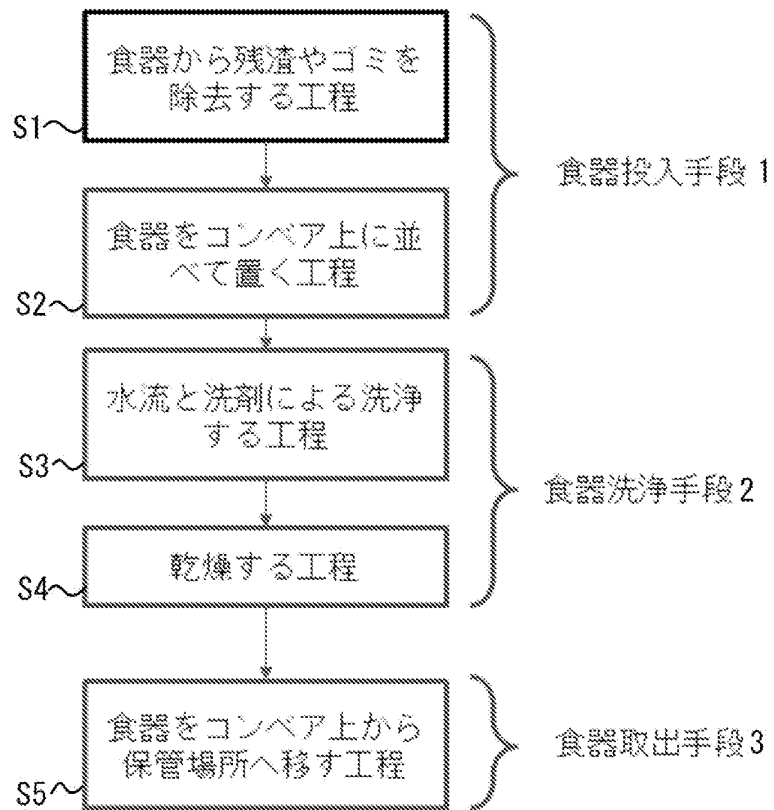


[図1]



[図2]

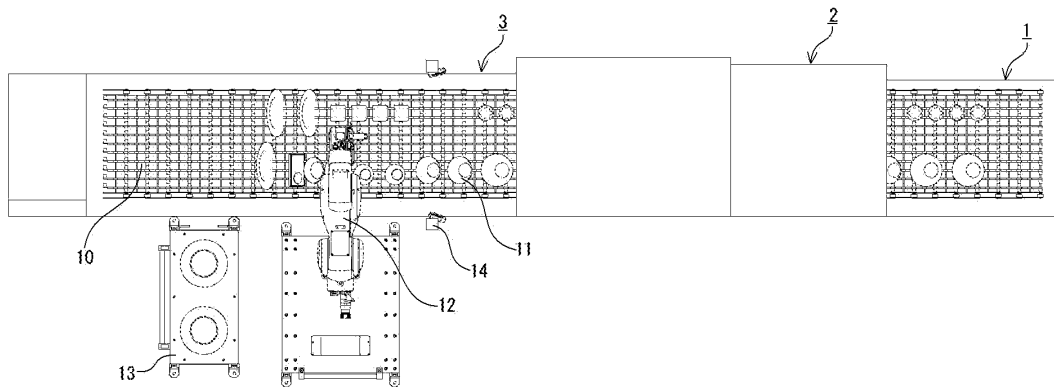


図2A

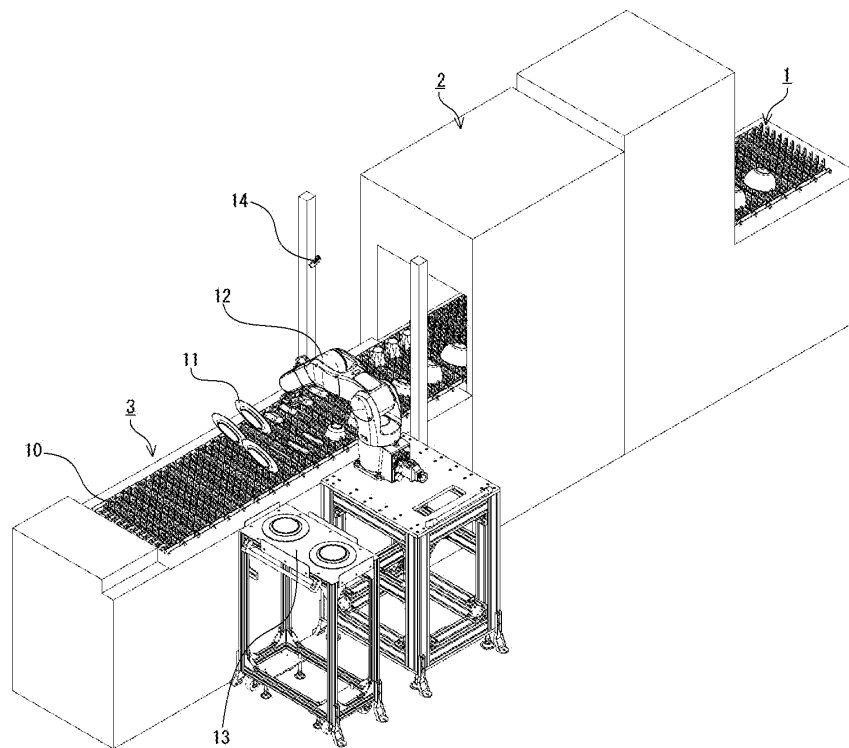
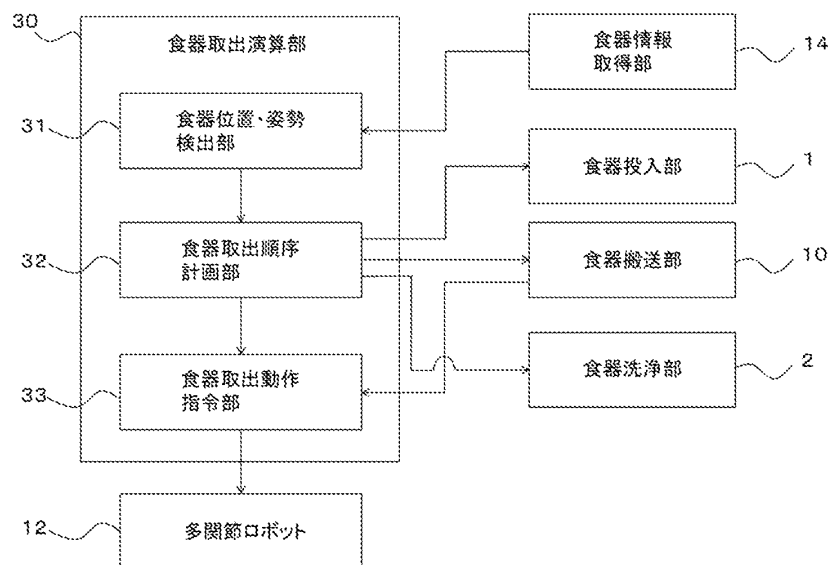


図2B

[図3]



[図4]

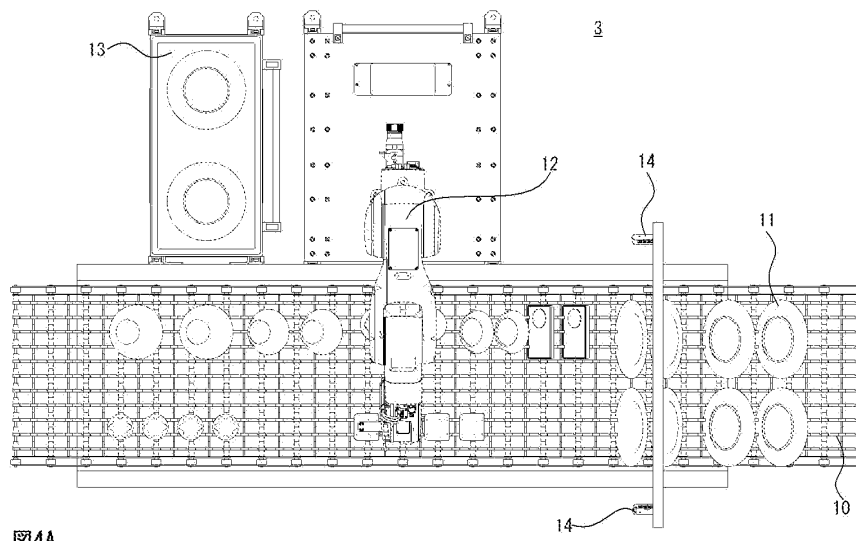


図4A

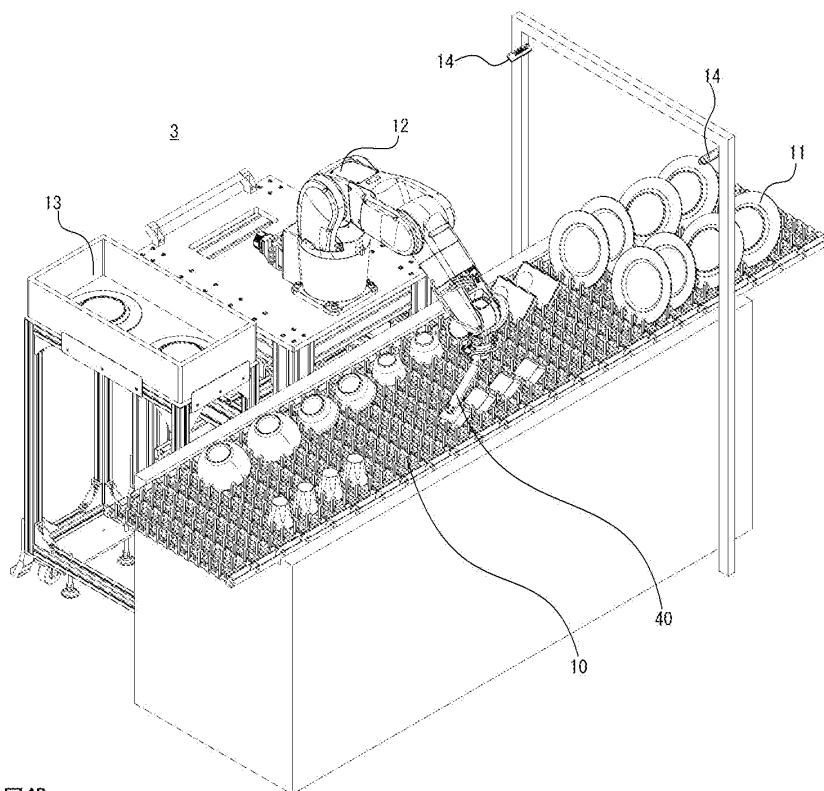
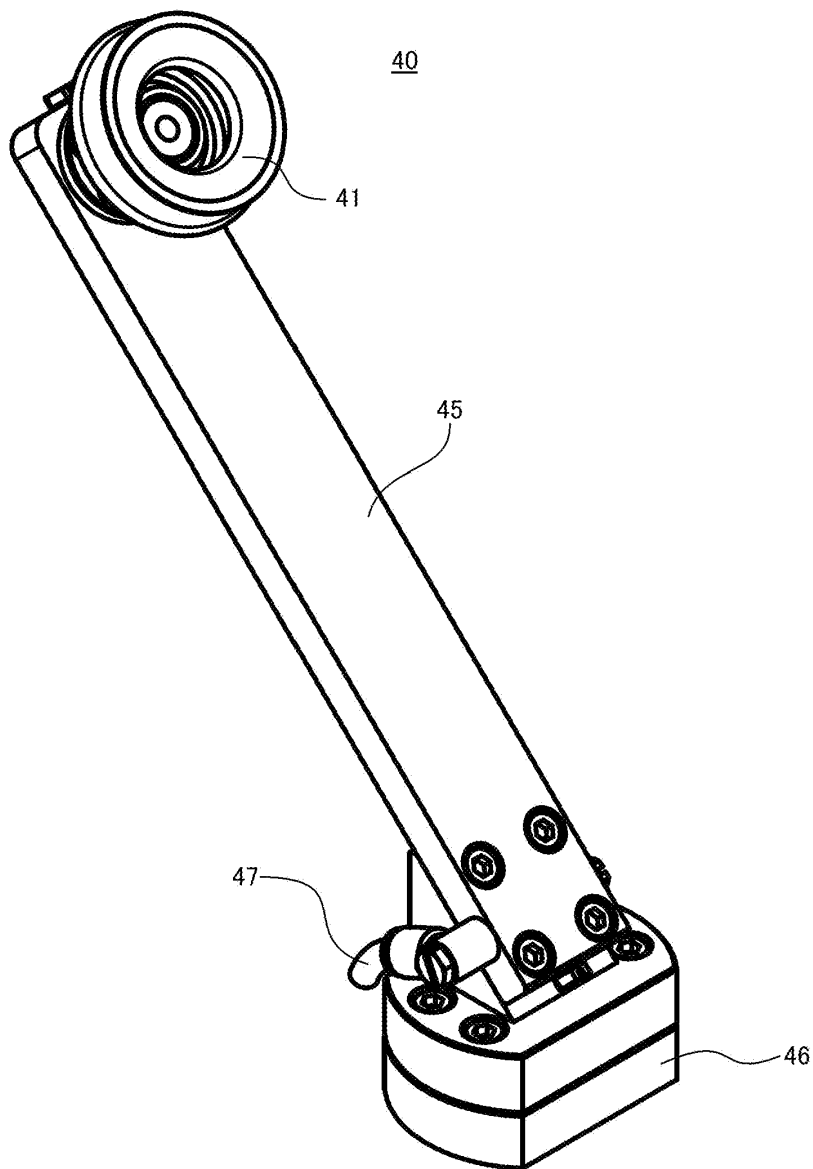


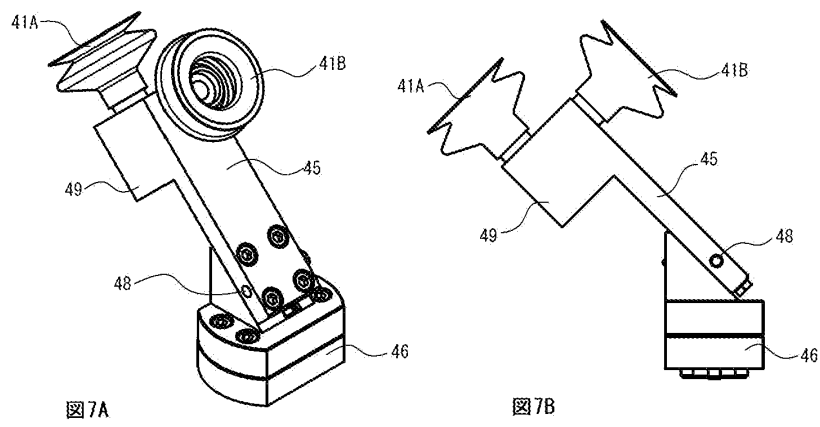
図4B

Figure 1 is a perspective view of a simulated environment 10. The environment includes a table 40, a chair 41, and a robot 42. A callout box 11 points to the robot, indicating it has an AR marker 42 attached. Other callout boxes identify components like '食器載置手段13' (Dish placement means 13), '多関節ロボット12' (Multi-joint robot 12), '食器情報取得手段14' (Dish information acquisition means 14), and '食器搬送手段10' (Dish transport means 10).

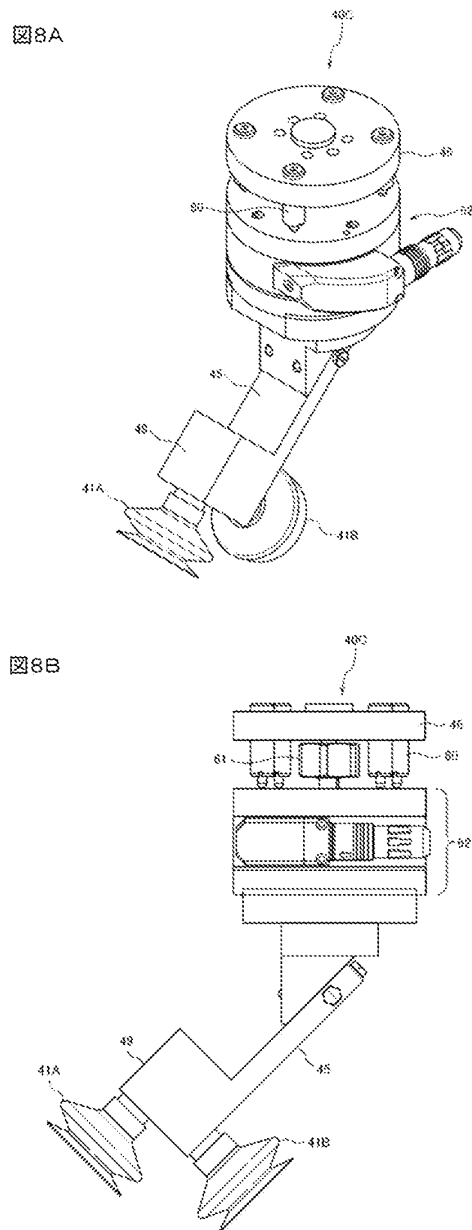
[図6]



[図7]



[図8]



[図9]

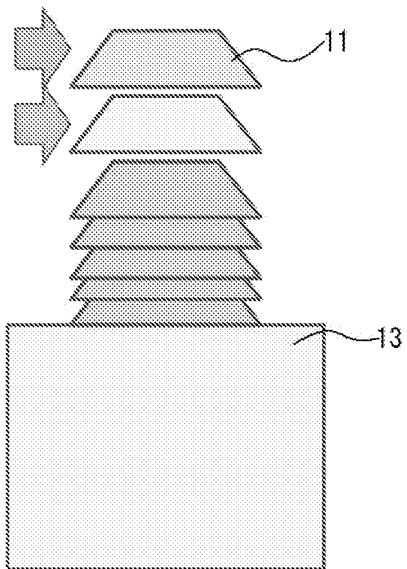


図9A

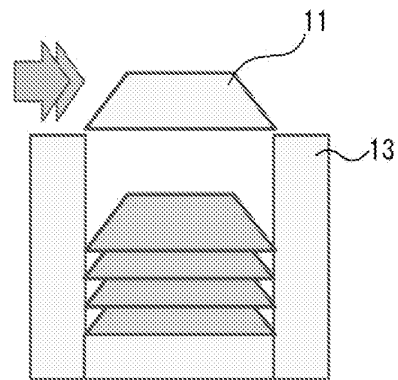


図9B

[図10]

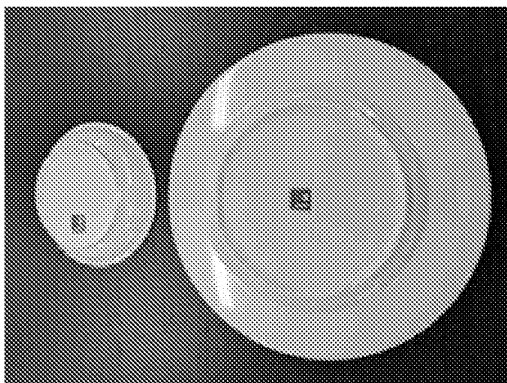


図10A

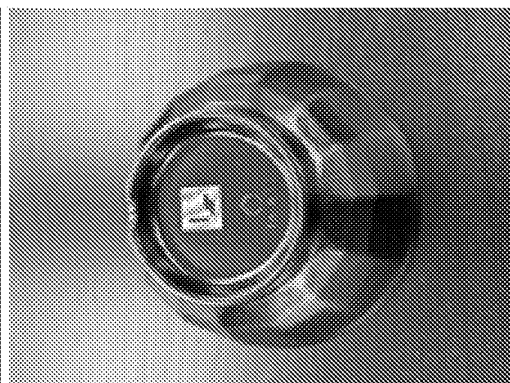


図10B

[図11]

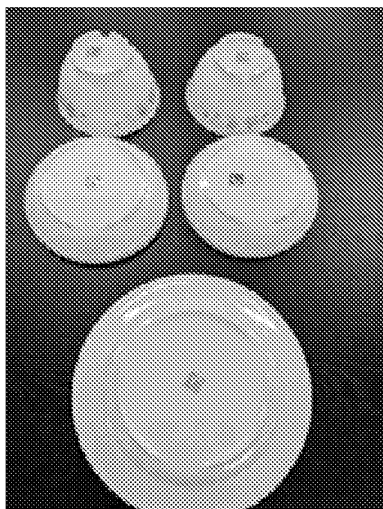
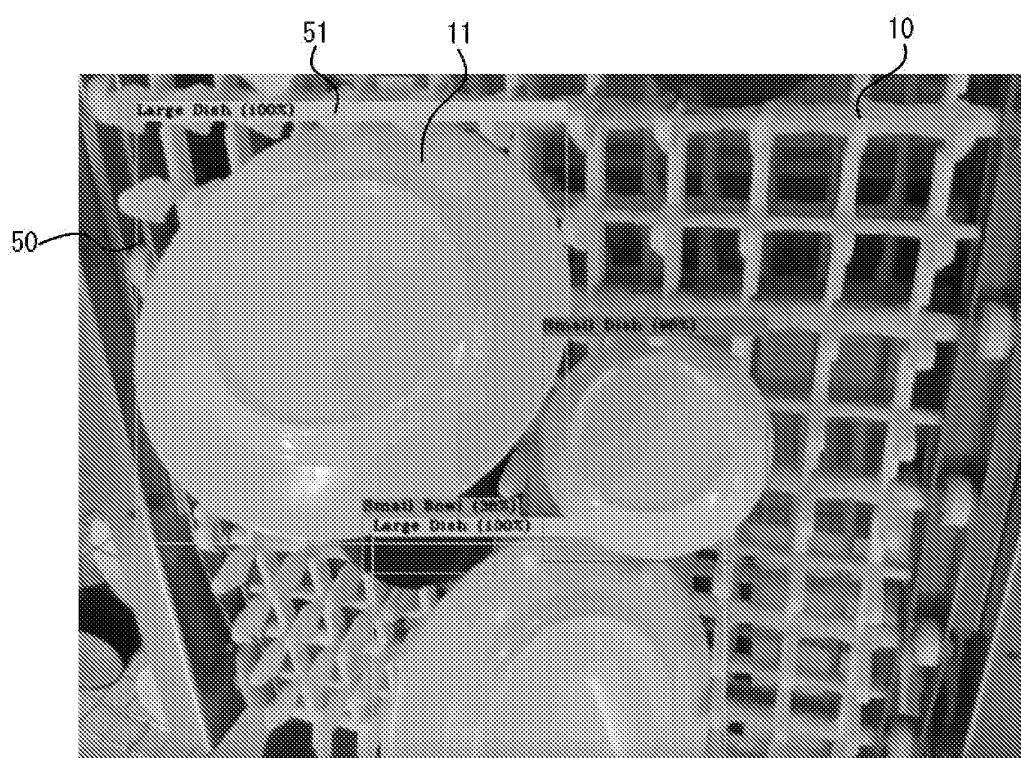


図11A

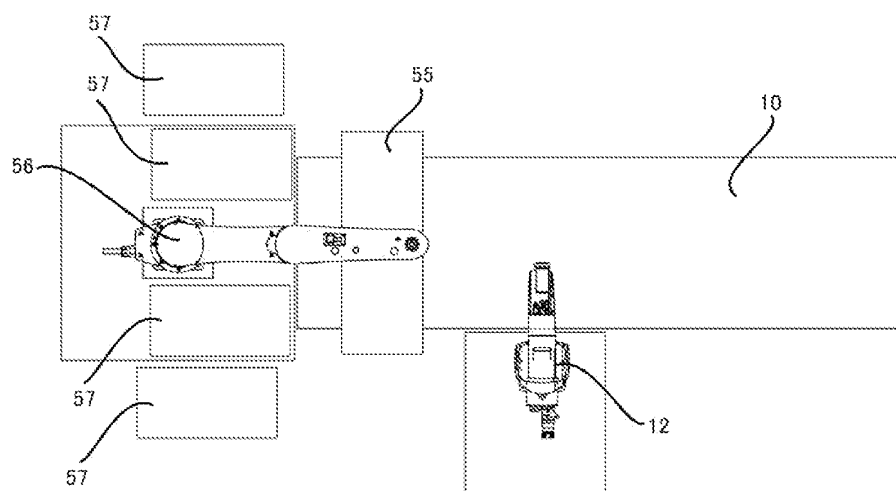


図11B

[図12]



[図13]



[図14]

図14A

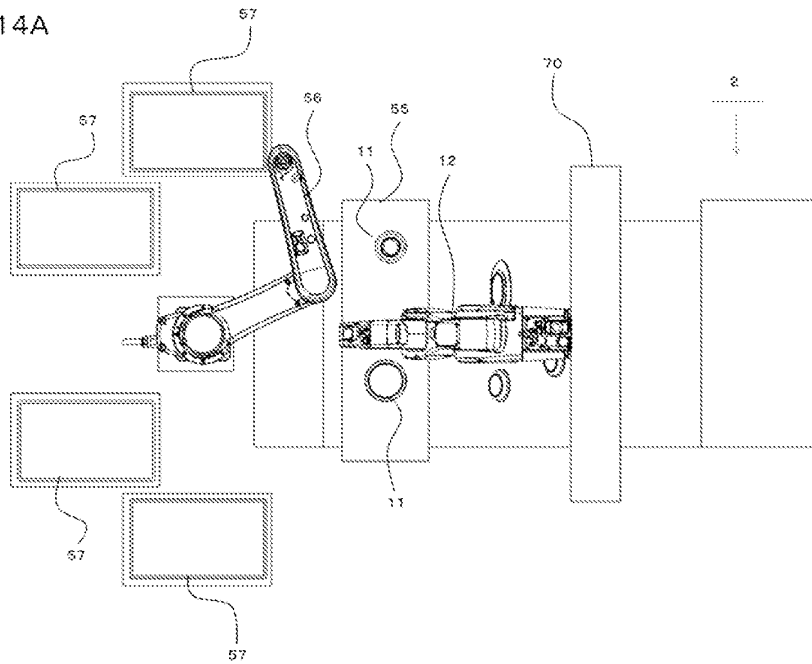
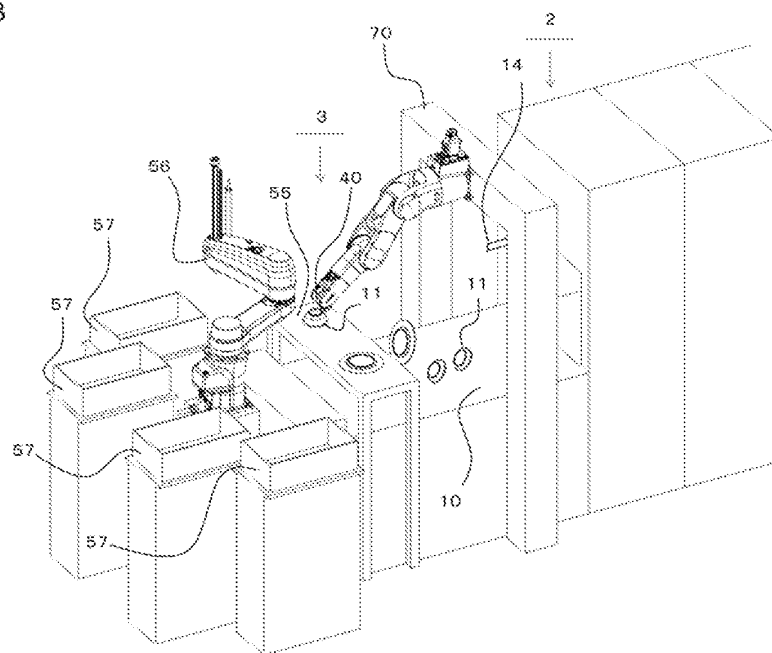


図14B



[図15]

