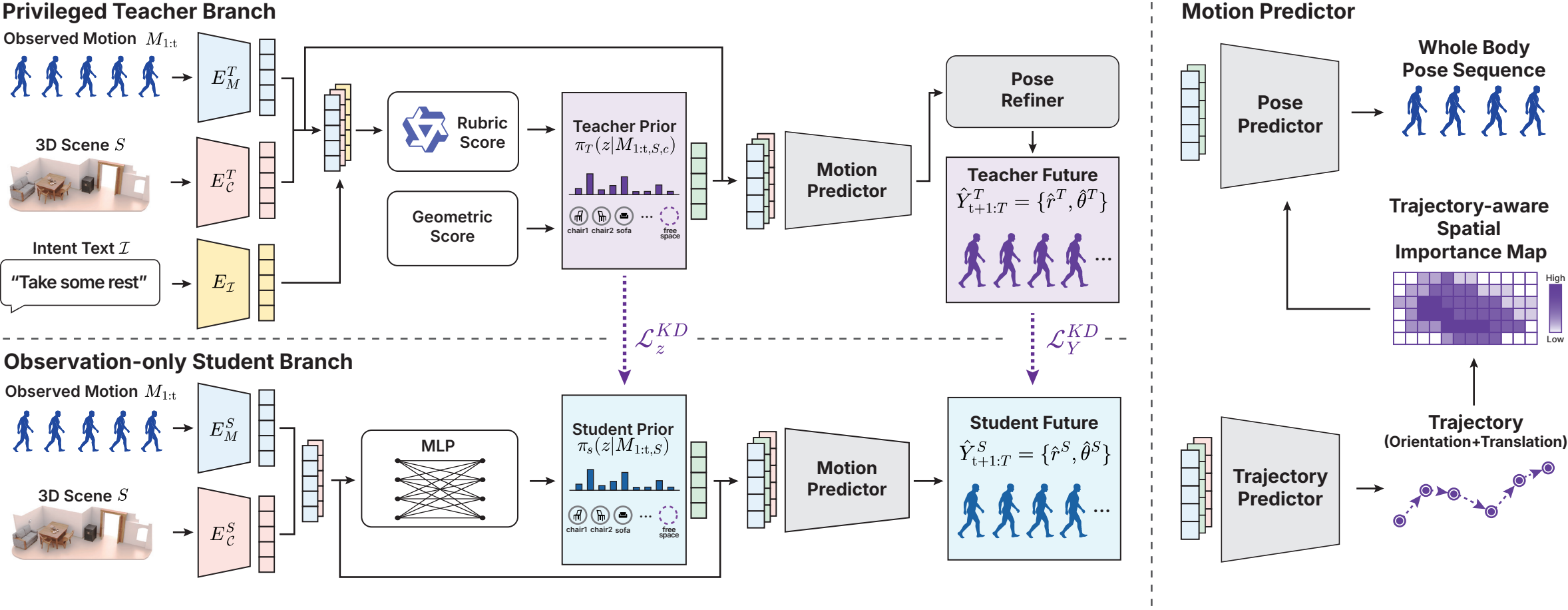

Privileged Teacher Branch
Observed Motion $M_{1:t}$
3D Scene S
Intent Text $\mathcal{I}$
"Take some rest"
E_M^T
E_C^T
$E_{\mathcal{I}}$
Rubric Score
Geometric Score
Teacher Prior
$\pi_T(z|M_{1:t,S,c})$
chair1 chair2 sofa
free space
Motion Predictor
Pose Refiner
Teacher Future
$\hat{Y}^T_{t+1:T} = \{\hat{r}^T, \hat{\theta}^T\}$
$\mathcal{L}_z^{KD}$
$\mathcal{L}_Y^{KD}$
Observation-only Student Branch
Observed Motion $M_{1:t}$
3D Scene S
E_M^S
E_C^S
MLP
Student Prior
$\pi_s(z|M_{1:t,S})$
chair1 chair2 sofa
free space
Motion Predictor
Student Future
$\hat{Y}^S_{t+1:T} = \{\hat{r}^S, \hat{\theta}^S\}$
Motion Predictor
Pose Predictor
Whole Body Pose Sequence
Trajectory-aware Spatial Importance Map
High
Low
Trajectory (Orientation+Translation)
Trajectory Predictor