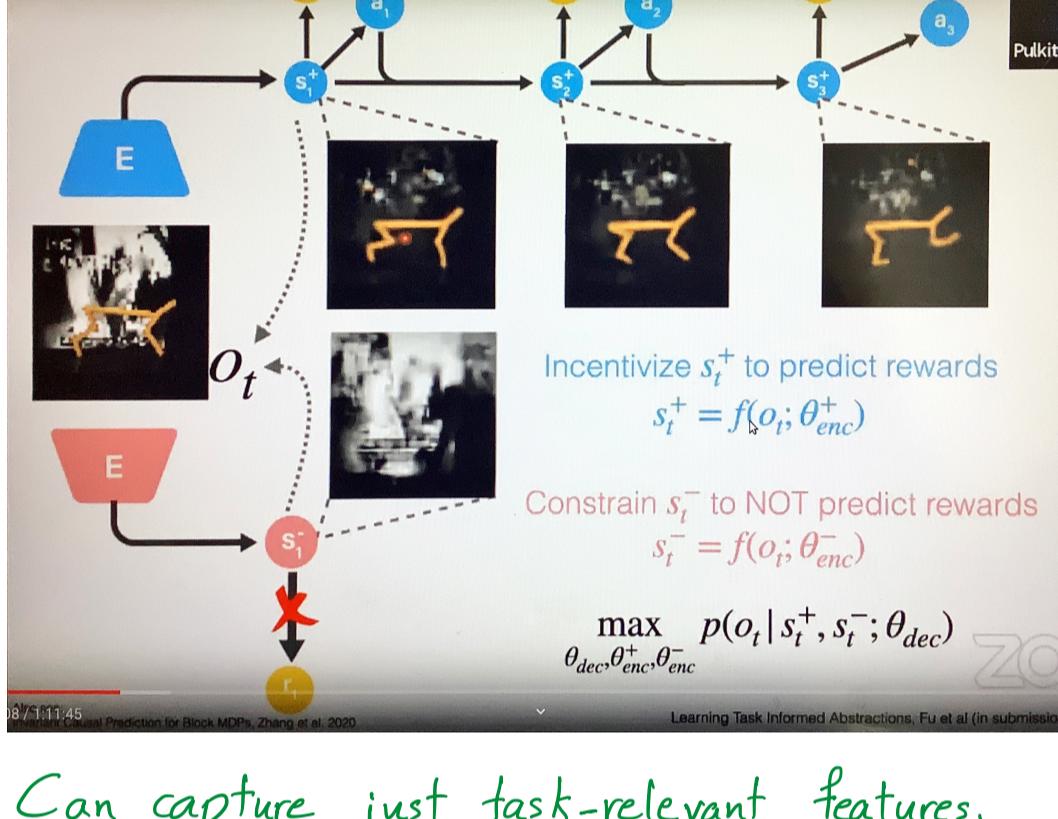
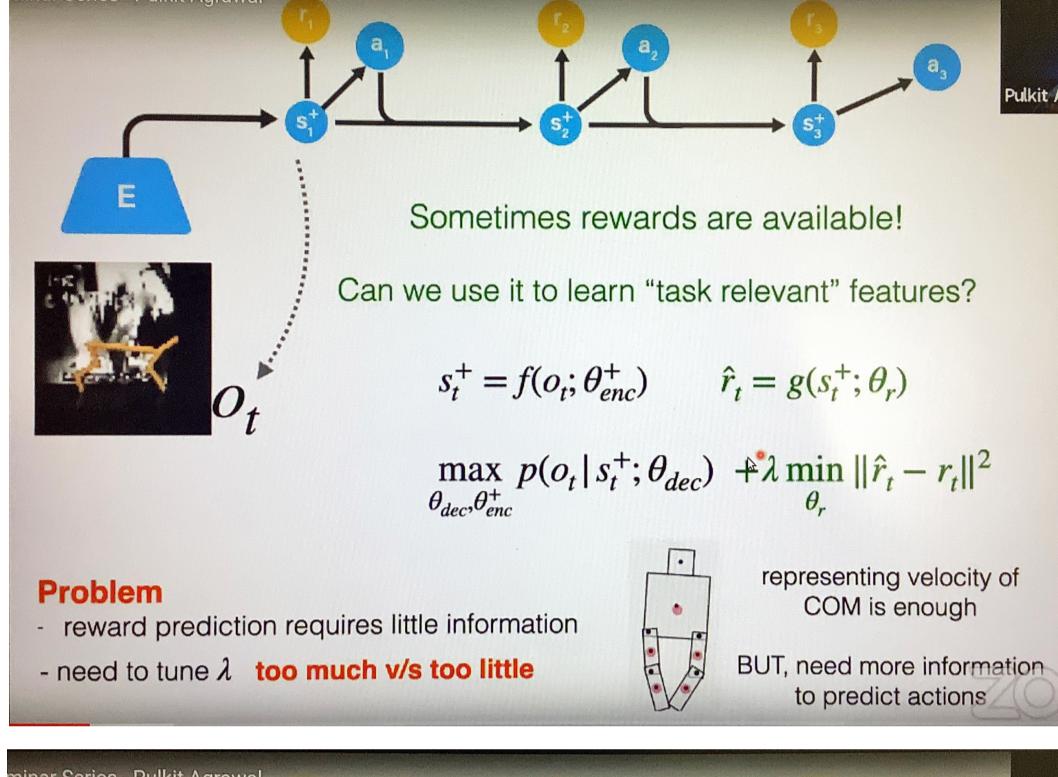


- Self-supervised robot learning:

- If we have reward function:

Learning task informed abstractions [Fu ..]



Can capture just task-relevant features.

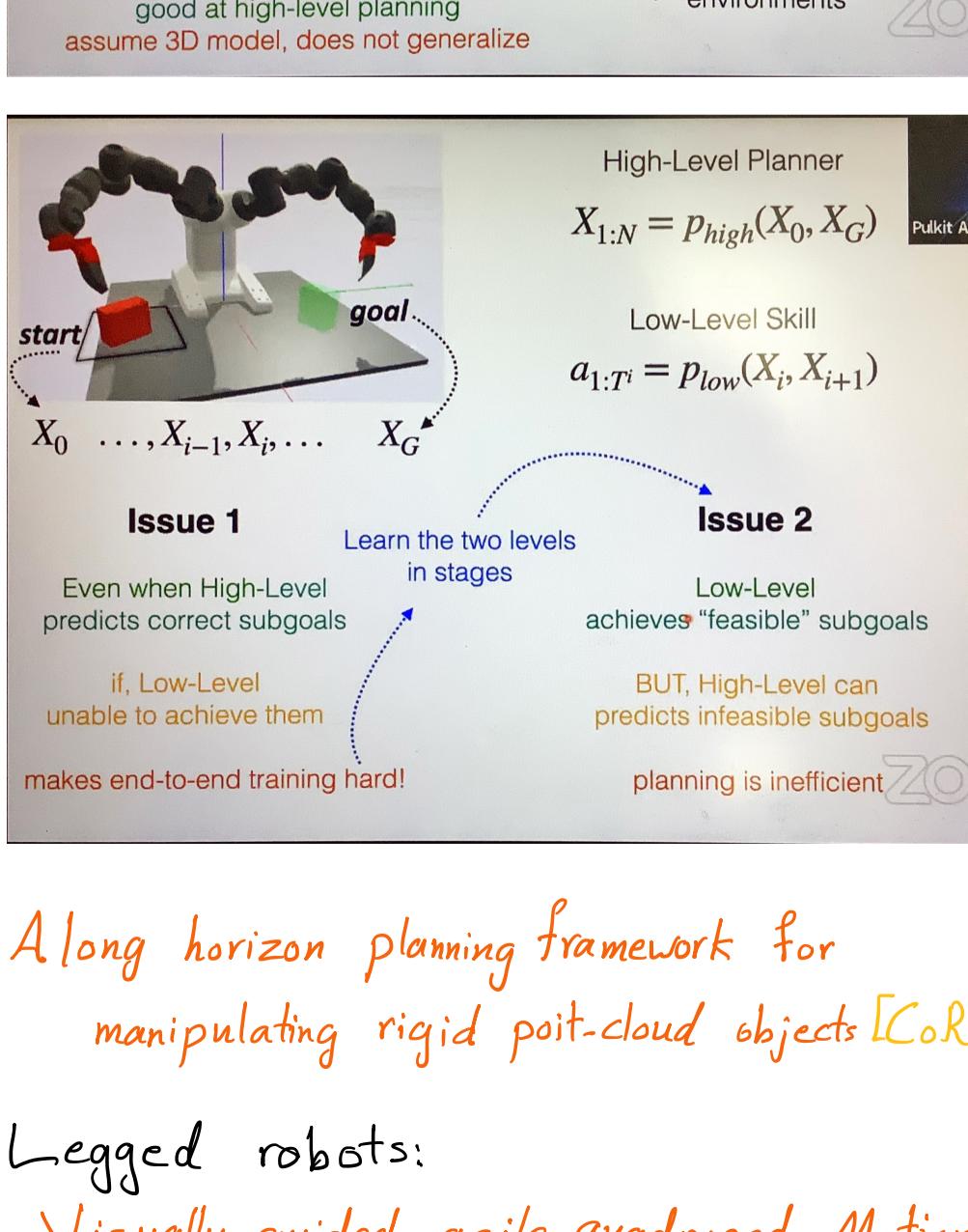
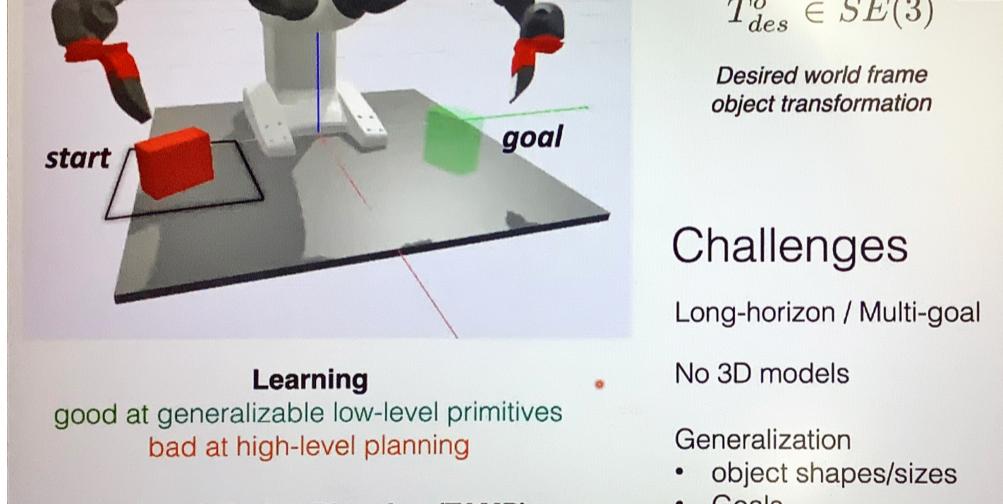
- No reward but demonstrations

Zero shot visual imitation [ICLR'18]

Forward Consistency Loss

GLAMOR [Pastor'20]

- Skill learning:



A long horizon planning framework for manipulating rigid point-cloud objects [CoRL'20]

- Legged robots:

Visually guided agile quadruped motion [Margolis ..]