

Summary

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February 1, 2022
Seminar on Continual Learning
Robotic Vision Lab

A Simple Approach to Continual Learning By Transferring Skill Parameters

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Introduction

Related Work They define contin

Simple Continual Learning with Skill Transfer

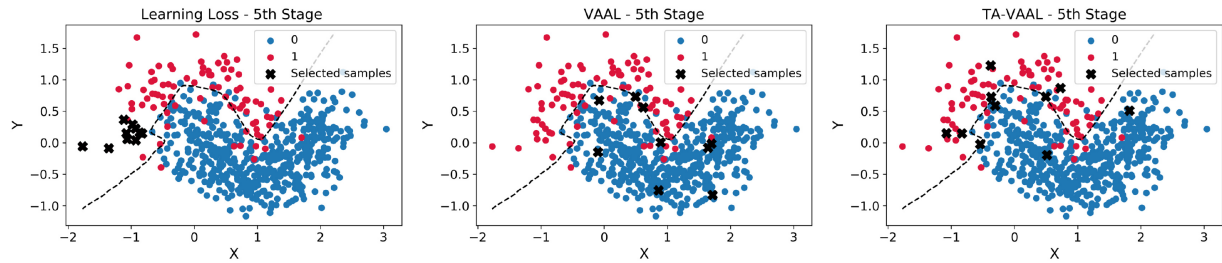


Figure 1: Visual results of active learning methods (Learning loss [40], VAAL [31], our TA-VAAL) on imbalanced toy example at the 5th stage. *Red* and *blue* dots indicate samples assigned to class 0 and 1, respectively. Ten samples at that stage (denoted by *black cross*) were selected using each method. The oracle decision boundary of the model is shown as a black dash line. Learning loss identified difficult samples near the decision boundary and VAAL found influential samples over the entire set. Our TA-VAAL selected samples that are both difficult (near decision boundary) and influential (over the entire set).

References