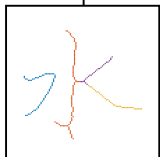


Image
Demonstrations



Priori
Trajectory

$l_j(v_{2t})$

Fuzzy
Gaussian
Mixture
Model

μ, Σ
 C, T, Q

$l_j(v_{1t})$

Time
Encoding

t_i

Image
Demonstrations

Skill
Learning

Deviation
Analysis

$\{z_t, R_t^z\}$

Gaussian
Mixture
Regression

$\{x_t, y_t\}$

Dynamic
Movement
Primitive

$\{x'_t, y'_t\}$

$\{z'_t, R_t^{z'}\}$

Inverse
Kinematics

Motion
Generalization

Environment
Variable

Robot
Manipulation

$\{\theta_t^i\}$

