# Active Learning ⋆

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**Abstract:** DPTA is a conceptual framework where the LLM's world knowledge is leveraged to analyze low-level sensor feedback, enabling the dynamic selection and refinement of complex, pre-learned robot trajectories to achieve high dexterity and resilience in autonomous manipulation.

*Keywords:* LLM, robotic, Reinforcement Learning

## 1. INTRODUCTION

We use world model to predict the future based on historical data. Hafner et al. (2019) world models allow for planning and behavior learning given only small amounts of real world interaction

## 2. BACKGROUND

### *2.1 Main challenges*

## 3. ARCHITECTURE

## DECLARATION OF GENERATIVE AI AND AI-ASSISTED TECHNOLOGIES IN THE WRITING PROCESS

During the preparation of this work the author(s) used NotbookLM and ChatGPT in order to help English as secondary language speaker. After using this tool/service, the author(s) reviewed and edited the content as needed and take(s) full responsibility for the content of the publication.

## REFERENCES

Hafner, D., Lillicrap, T., Ba, J., and Norouzi, M. (2019). Dream to control: Learning behaviors by latent imagination. *arXiv preprint arXiv:1912.01603*.

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