

**CO885 – Workshop 2**  
**“How to read and synthesise the literature?”**  
*Rogério de Lemos*

**Participative exercise: write an abstract**

- ❑ The goal of this exercise is for you to write an abstract of an existing paper.
- ❑ A well known and accessible paper from Computer Science has been selected, and the request is for you **not** to search for the original publication, which contains its original abstract. Instead, download the paper from Moodle (the abstract has been removed), read the paper, and write your version of the abstract.
- ❑ For writing the abstract follow the Koopman guidelines discussed during the workshop.
- ❑ Towards the end of the workshop, several submitted abstracts will be presented and discussed, including the original abstract.
- ❑ This is an individual effort, and the abstract should be submitted on Moodle using this form
- ❑ Deadline: 4pm on the day of the workshop

1. This is an individual submission:

Name	Login	Which MSc?
Pierre-Marie DANIEAU	PRLD2	Advanced Computer Sciences (computational intelligence)

2. Read the following paper (available on Moodle):

Pattie Maes and Rodney A. Brooks. 1990. Learning to coordinate behaviors. In Proceedings of the eighth National conference on Artificial intelligence - Volume 2 (AAAI'90), Vol. 2. AAAI Press 796-802.

3. Write the abstract (150 to 200 words):

At the MIT Mobile Robot group, we found a need way to give the robot algorithm to have a behaviour. The robots learn their behaviour instead of behind programmed directly for each types of input. The learning process is based on a good / bad feedback for a certain behaviour made. In the processing of learning, the robot will try to understand if it which behaviour to reproduce for each condition. This learning process is based on an algorithm that allow to have behaviours that are relevant and reliable.

To do so, we have created Genghis, a robot with 6 legs with one task: walk forward. Based on the different feedback and with *some* time, Genghis learned by itself to go from a point A to B. Our future goal is to go forward and test this algorithms on multiple and different robots to see if the algorithm is still relevant and reliable depending on the sensors and behaviour possible.