**Apprenticeship Learning (AL) via Inverse Reinforcement Learning (IRL) –**

<https://jangirrishabh.github.io/2016/07/09/virtual-car-IRL/>

While ordinary "reinforcement learning" involves using rewards and punishments to learn behavior, in IRL the direction is reversed, and a robot observes a person's behavior to figure out what goal that behavior seems to be trying to achieve.

Apprentiship learning via inverse reinforcement learning will try to **infer the goal of the teacher**. In other words, it will learn a reward function from observation, which can then be used in reinforcement learning. If it discovers that the goal is to hit a nail with a hammer, it will ignore blinks and scratches from the teacher, as they are irrelevant to the goal.

A robot observes the expert demonstration and then tries to figure out what the goal is, building its own reward function via IRL.

