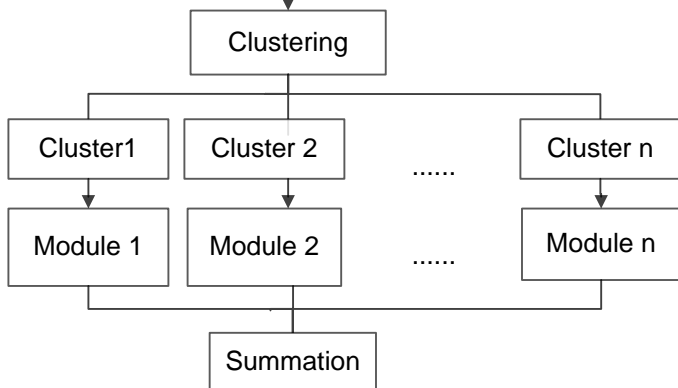


1. Human Demonstration in different contexts



$\{F, T, s\}$: object level exert force,
object level exert torque,
object movement

2. Model Learning



3. Robot Control

$\{F, T\}$: object level exert force
(converted to robot joint torque)

