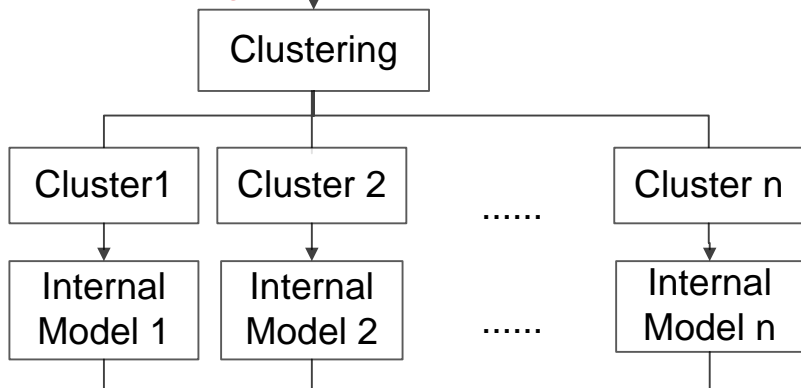# 1.Human Demonstration in different contexts

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

2.Model Learning

Clustering

| Cluster1 | Cluster 2 | ...... | Cluster n |

| Internal Model 1 | Internal Model 2 | ...... | Internal Model n |

3.Robot Control

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