

Human Demonstration



Exert Force /
Object movement

Clustering

Cluster1

Cluster 2

.....

Cluster n

Internal
Model 1

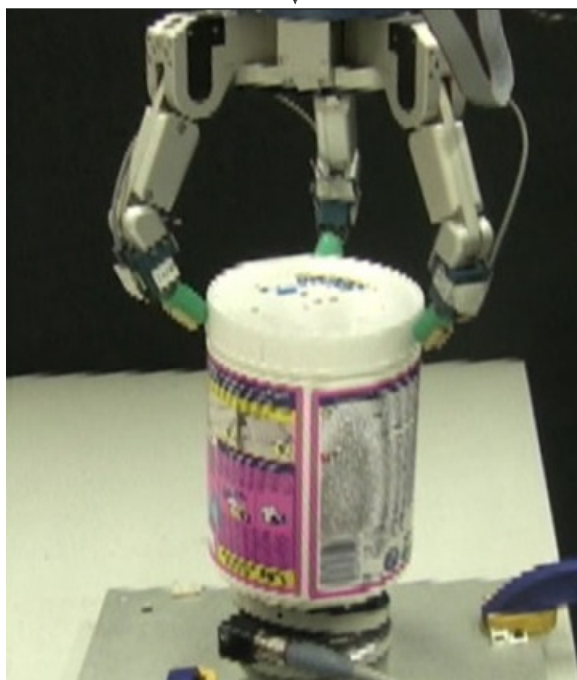
Internal
Model 2

.....

Internal
Model n

Exert Force
(adapt to current task context)

Robot hand
Jacobian



Robot control policy