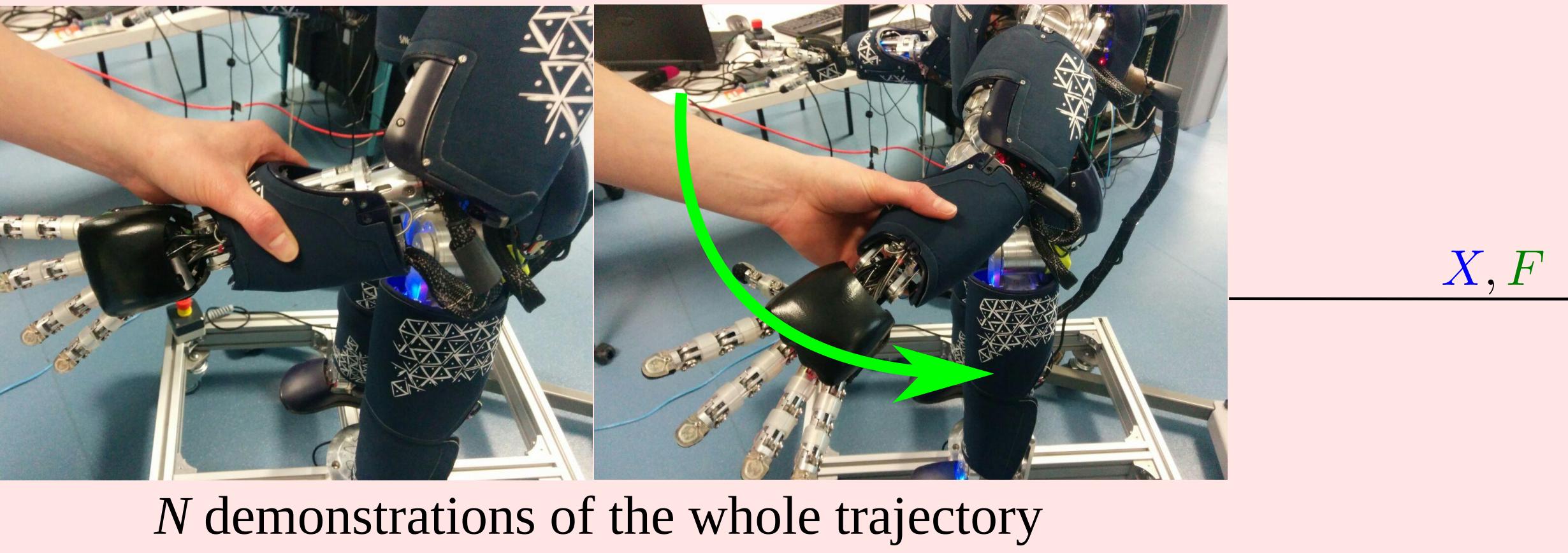


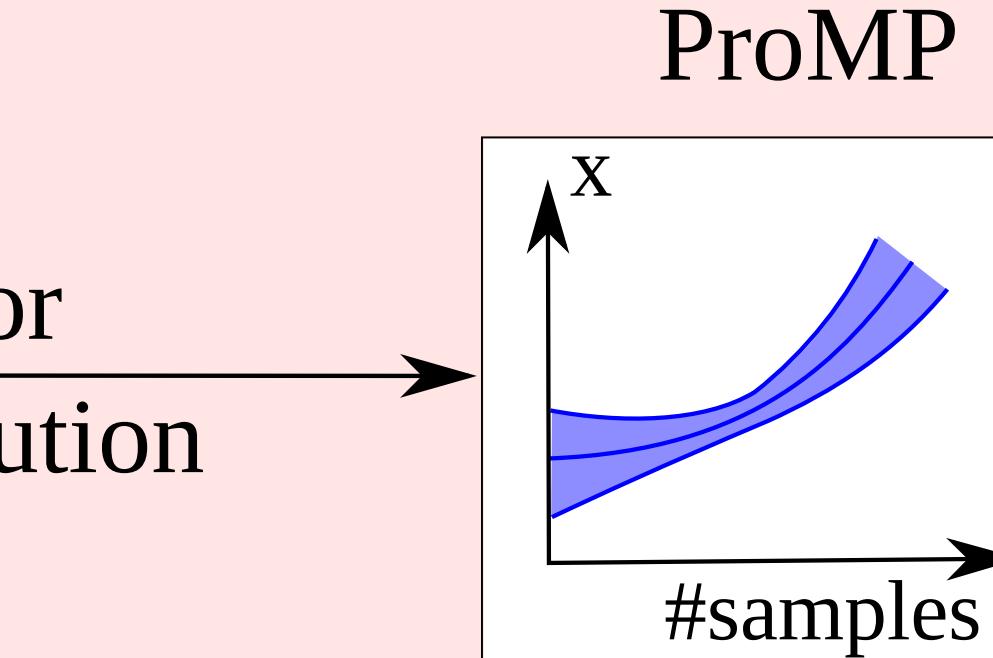
Training



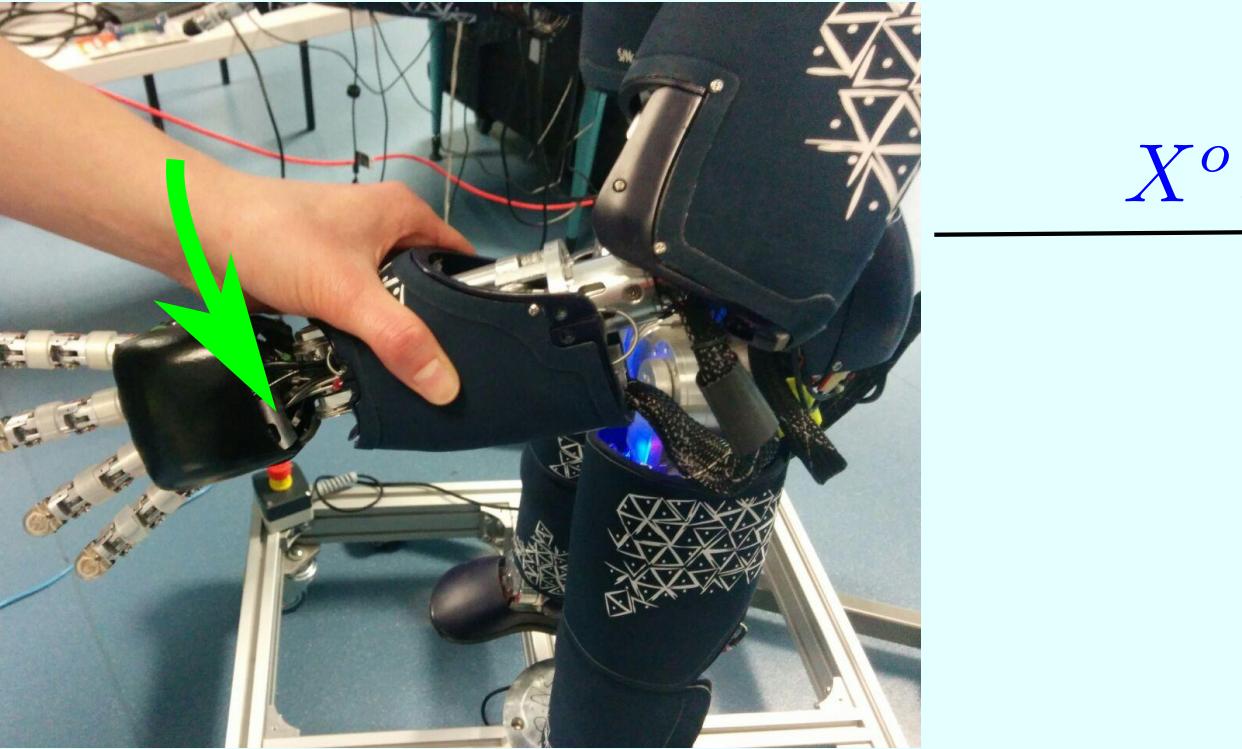
Model learning

$$\Phi_t^\top \begin{bmatrix} \omega_X \\ \omega_F \end{bmatrix} + \epsilon_{X,F}$$

computing $\omega \sim \mathcal{N}(\mu_\omega, \Sigma_\omega)$

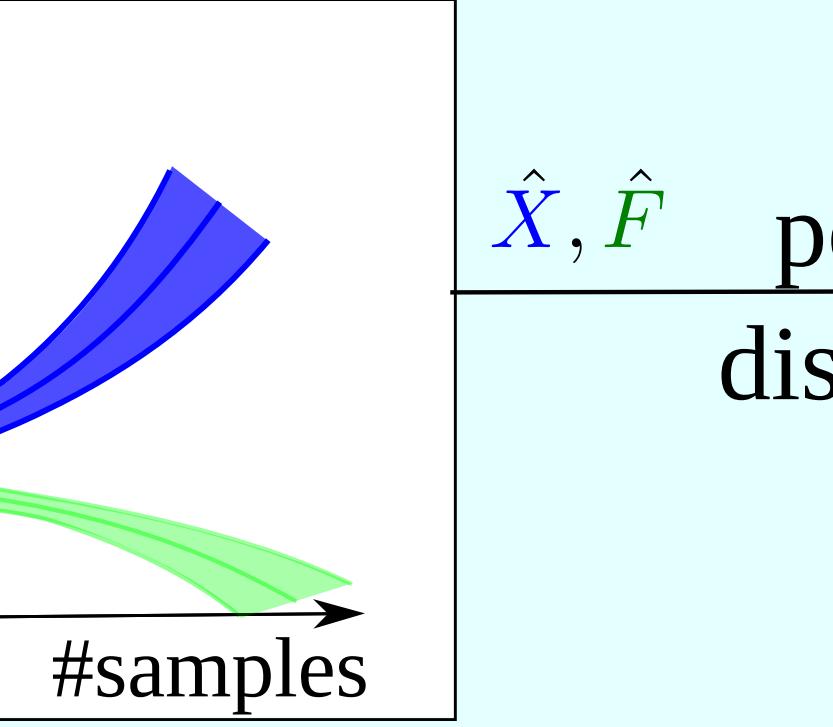


Inference



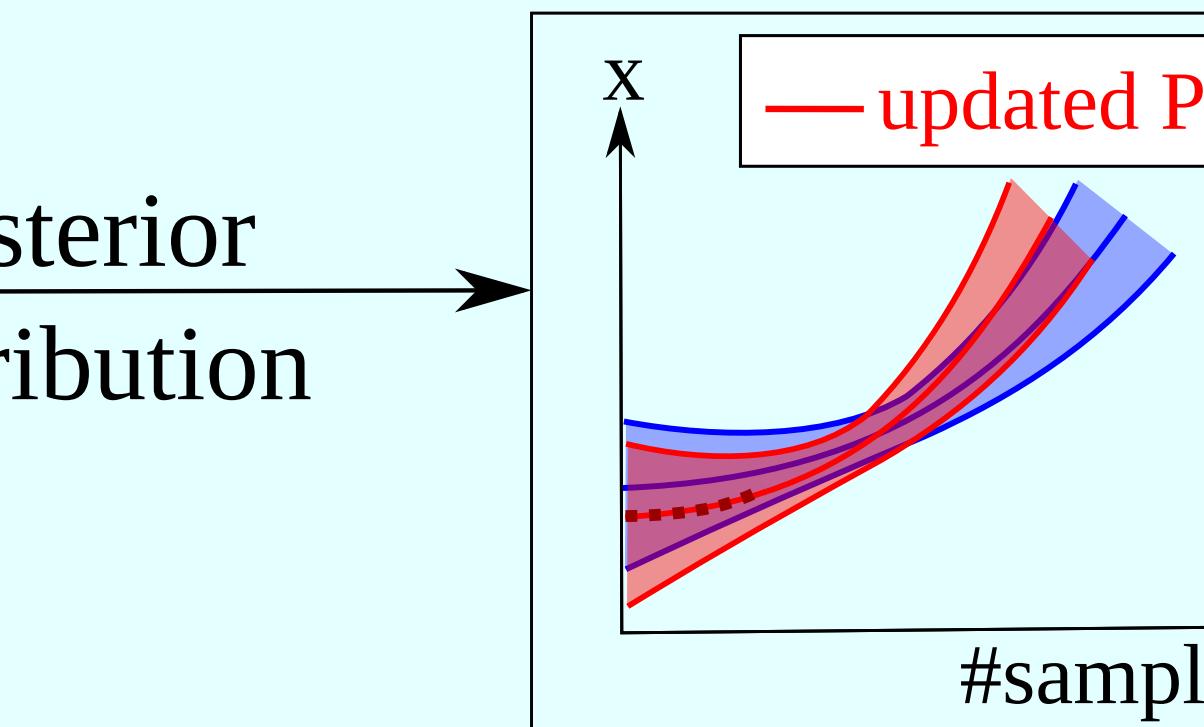
Movement initiated by the partner

ProMP recognition



observations
recognized ProMP

Model update



computing $\hat{\omega} \sim \mathcal{N}(\hat{\mu}_\omega, \hat{\Sigma}_\omega)$

Movement finished
by the robot autonomously

