

# Guilherme Maeda

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## Contact Information

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## Motivation and Research

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Robots will eventually become part of our daily lives and will help us by physically interacting with us and with our world. Part of the reason robots are still confined to the industrial environment is because they are not capable of learning tasks by themselves. Currently, robots rely on a specialized technician to pre-program decision rules and movements. I investigate algorithms that enable robots to find the solutions of tasks by observing, representing, imitating, and improving human actions. Such investigations revolve around three main topics.

**Robot learning:** Imitation learning, reinforcement learning, optimization using physical agents. Representation and (active) learning of movement primitives, probabilistic modeling, and observational learning

**Semi-autonomous robots:** Collaborative and assistive robotics, physical human-robot interaction, comfort and ergonomic aspects in interaction, human-robot joint skill learning, interactive learning

**Planning and control:** Motion planning, trajectory optimization, adaptive control, iterative learning and repetitive control, system identification

## Education

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### PhD in Field Robotics

July 2009 – November 2013

“Learning and Reacting with Inaccurate Prediction: Applications to Autonomous Excavation”

Australian Centre for Field Robotics. The University of Sydney, Australia

*Advisors:* Hugh Durrant-Whyte, David Rye, Ian R. Manchester, Surya Singh

*Thesis examiners:* Kevin Moore (Colorado School of Mines), Peter Corke (Queensland University of Technology), Quang Ha (University of Technology Sydney)

### Masters in Control Engineering

2004 – 2007

“Ultra-precision Positioning Control using a Conventional Ball-screw Mechanism”

Tokyo Institute of Technology, Japan

*Advisor:* Kaiji Sato

### Bachelors in Mechanical Engineering, Automation and Systems

1998 – 2003

“Automatic Pressure Control of Lung Ventilators with Regenerative Compressor”

The University of Sao Paulo, Brazil

## Honours, Awards and Research Funding

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### Finalist: Best Paper, Best Student Paper, and Best Service Robotics Paper

2015

At the 2015 IEEE International Conference on Robotics and Automation (ICRA).

### KUKA Innovation Award 2015 Sponsored Track

2015

Awarded with the deployment of a KUKA LBR iiwa (approx. € 100,000) with the proposal “A Personal Robot Assistant for Home and Industry” during the competition period.

**Doctoral Research Scholarship** 2009–2013  
Awarded by The University of Sydney and the Rio Tinto Centre for Mining and Automation.

**Outstanding Young Researcher** 2006  
Awarded at the International Conference on Leading Edge Manufacturing (LEM 21).

**Master's Degree Scholarship** 2005–2007  
Awarded by the Japanese Ministry of Education, Culture, Sports, Science and Technology.

## Professional Experience

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**Researcher** May 2019 – present  
Preferred Networks, Inc. Tokyo, Japan

- Research in machine learning and robot control for human support tasks
- Patent applications and dissemination of relevant work in international conferences and as journal publications
- Mentoring of internship students

**Research Scientist** November 2017 – April 2019  
ATR Computational Neuroscience Laboratories, Dept. of Brain Robot Interface, Kyoto, Japan

- Research in machine learning, humanoid control, and human-robot collaboration
- Advising of graduate students and internship students
- Robotics demonstrations

**Research Scientist and Team Leader** November 2013 – October 2017  
Intelligent Autonomous Systems, Technische Universitaet Darmstadt, Darmstadt, Germany

- Research in machine learning and control methods with an emphasis on human-robot collaboration and semi-autonomous robots
- Advising of PhDs (4), Masters (2) and Bachelor (7) students
- IAS team leader for the EU-funded 3rd Hand Robot Project
- Co-lecture and invited lectures on machine learning, robotics and control

**Research Assistant** April 2013 – October 2013  
Australian Centre for Field Robotics, Sydney, Australia

- Model-predictive control and motion planning algorithms for autonomous driving of car-like robots
- Field trials in remote and open environments

**Research & Development** 2007 – 2009  
IHI Corporation (Former Ishikawajima-Harima), Tokyo, Japan

- Mechanical design of robot end-effectors and precision roller printers
- Concept, design and evaluation of transportation systems in assembly lines

**Research & Development** 2002 – 2004  
Intermed Medical Equipment, Sao Paulo, Brazil

- Design of centrifugal pumps control for portable lung ventilators
- Mechanical and control design of anaesthesia equipment

## Invited Talks

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**Nagoya University** **October 2017**  
Department of Micro-Nano Mechanical Science and Engineering. Chaired by Prof. Jun Nakanishi.

**IEEE/RSJ Int. Conference on Intelligent Robots and Systems (IROS)** **September 2017**  
24/09/2017. Invited speaker. Workshop: Learning for Collaborative Robotics: Enabling Flexible, Redeployable and Agile Industrial Applications. Vancouver, Canada.  
24/09/2017. Invited speaker. Workshop: Human in-the-loop robotic manipulation. Vancouver, Canada.  
28/09/2017. Invited speaker. Workshop: Joint Learning in Human-Robot Collaboration. Vancouver, Canada.

**European Robotics Forum (ERF)** **March 2017**  
Invited speaker. Workshop: Teaching by Demonstration for Industrial Applications. Edinburgh, Scotland.

**Queensland University of Technology (QUT)** **February 2017**  
Brisbane, Australia. Chaired by Prof. David Lovell.

**Advanced Telecommunications Research Institute International (ATR)** **February, 2017**  
Kyoto, Japan. Chaired by Dr. Jun Morimoto.

**Inria-Bordeaux** **January 2017**  
Bordeaux, France. Chaired by Dr. Pierre-Yves Oudeyer.

**University of Edinburgh** **May 2016**  
Edinburgh, Scotland. Chaired by Prof. Barbara Webb.

**SQUIRREL-3rdHand Winter school** **February 2016**  
Oberurg, Austria. Chaired by Michael Zillich.

**Plymouth University** **November 2015**  
Plymouth, England. Chaired by Prof. Angelo Cangelosi.

**International Conference on Humanoid Robots (HUMANOIDS)** **November 2014**  
Invited speaker. Workshop: Policy Representation for Humanoid Robots. Madrid, Spain. Chaired by Neil Dantam.

## Organization of Workshops

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**International Conference on Intelligent Robots and Systems (IROS)** **2016**  
Full-day workshop: Towards Co-Adaptive Learning Through Semi-Autonomy and Shared Control. Organized with Luka Peternel (IIT). Co-organizers: Leonel Roza (ADVR, IIT, Italy), Serena Ivaldi (INRIA Nancy Grand-Est, France), Claudia Pérez D'Arpino (MIT, USA), Julie A. Shah (MIT, USA), Jan Babič (ABR, JSI, Slovenia), Tamim Asfour (KIT, Germany), Erhan Oztop (Ozyegin University, Turkey) and Jan Peters (TU Darmstadt, Germany).

## Teaching Experience

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**Co-Teaching: Machine Learning 1– Statistical Approaches** **2015, 2016, 2017**  
TU Darmstadt. (~ 100 students).  
Topics: Probability, information theory and entropy. Bayesian decision theory. Kernel methods and Gaussian

Process. Linear discriminant analysis, perceptron, logistic regression.

**Co-Teaching: Robot Learning Course**

**Fall 2015, 2016**

TU Darmstadt (~60 students).

Topics: foundations for optimal decision making, MDPs, dynamic programming

**Guest Lecturer: Intelligent Multi-Agent Systems**

**Spring 2015**

Invited by Gerhard Neumann. TU Darmstadt. (~ 20 students)

**Teaching Assistant: Introduction to Mechatronics (MTRX1701)**

**2010 – 2011**

The University of Sydney. Tutoring and grading. (~ 50 students)

**Instructor Computer-Aided Design (CAD) Software**

**1999 – 2000**

The University of Sao Paulo, Brazil.

Instructor and tutor of CAD software for first-year engineering students. (~ 60 students)

## Student Supervision

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### Doctoral

**2017. Carlos Celemin.** *Human Corrective Advice in the Policy Search Loop.* The University of Chile and Delft University of Technology. External visiting student.

**2014-2018. Okan Koc.** *Learning Robot Control for Aggressive Striking and Hitting Movements.* Max Planck Institute for Intelligent Systems, Germany. Co-supervised with Prof. Jan Peters.

**2014-present. Marco Ewerton.** *Bi-directional Human-Robot Learning for Sport Science Applications.* TU Darmstadt, Germany. Co-supervised with Prof. Jan Peters.

**2013-2017. Rudolf Lioutikov.** *Automatic Movement Segmentation and Skill Library Generation.* TU Darmstadt, Germany. Co-supervised with Prof. Jan Peters.

### Masters

**2019. Joni Väättäin.** *Automatic Extraction of Task Semantics From Observations.* PFN, Japan. Internship student from Waseda University (as main advisor and co-advised with Hironori Yoshida).

**2019. Zhangwei Hong.** *Off-policy Reinforcement Learning.* PFN, Japan. Internship student (Acting as co-advisor and advised by Prabhat Nagarajan).

**2019. Alaa Maghrabi.** *Combining Multiple Robot Skills via SLAM for Robotic Basketball.* ATR, Japan. Visiting student from EPFL (advisor: Auke Ijspeert).

**2018. Christina Aigner.** *Learning from Visual Observations of Human Interaction: 3D Skeleton Reconstruction via Kinect and OpenPose.* ATR, Japan. Visiting student from TU Munich (advisor: Gordon Cheng).

**2015-2016. Dorothea Koert.** *Combining Human Demonstrations and Motion Planning for Movement Primitive Optimization.* TU Darmstadt, Germany. Co-supervised with Prof. Jan Peters.

**2013-2014. Marco Ewerton.** *Modeling Human-Robot Interaction with Probabilistic Movement Representations.* TU Darmstadt, Germany. 2014. Co-supervised with Prof. Jan Peters and Prof. Gerhard Neumann.

## Bachelors

**2017. Claudia Lolkes** Thesis topic: Incremental Imitation Learning with Estimation of Uncertainty. TU Darmstadt, Germany.

**2017. Idris Nematpur** Thesis topic: Jointly Learning from Demonstrations and Human Preferences On Non-Linear Systems. TU Darmstadt, Germany.

**2015–2016. Daniel Alte** Thesis topic: Using a low-cost BCI device for intelligent control of a robotic arm. TU Darmstadt, Germany.

**2015 May-July. Aayush Maloo.** Advanced Project: Predictive Human-Robot Interaction for Assembly Tasks. TU Darmstadt, Germany. 2015. Visiting student from Indian Institute of Technology Madras, India under DAAD scholarship.

**2014–2015. Dorothea Koert.** Advanced Project: Inverse Kinematics for Optimal Human-robot Collaboration. TU Darmstadt, Germany.

**2014–2015. Markus Sigg and Fabian Faller.** Advanced Project: Sequencing of DMPs for Task and Motion Planning. TU Darmstadt, Germany. Co-supervised with Rudolf Lioutikov.

## Academic Service

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### Program Committee, Area Chair and Associate Editor

Area Chair: International Conference on Robot Learning (CoRL); 2018, 2019

Associate Editor.: International Conference on Robotics and Automation (ICRA); 2018

Associate Editor.: IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS); 2014, 2015, 2016, 2017, 2018

Program Committee: International Symposium on Experimental Robotics (ISER); 2016

### Reviewer of Journal Articles and Peer-Reviewed Conference Articles

International Journal of Robotics Research (IJRR). 2017, 2018, 2019, 2020

IEEE Transactions on Robotics (TRO). 2015, 2017, 2018, 2019

Autonomous Robots (AURO). 2014, 2017, 2018, 2019

IEEE Robotics and Automation Letters (RA-L). 2017, 2018, 2019

International Journal of Social Robotics (IJSR). 2018

IEEE Transactions on Automation Science and Engineering. 2013

Advanced Robotics. 2017

Automation in Construction. 2020

Neural Information Processing Systems (NIPS). 2014

International Joint Conference on Artificial Intelligence (IJCAI). 2016

Robotics: Science and Systems (RSS). 2015, 2016

International Symposium on Robotics Research (ISRR). 2015

International Symposium on Experimental Robotics (ISER). 2016

IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS). 2010, 2011, 2012, 2014, 2015, 2019, 2020

IEEE International Conference on Robotics and Automation (ICRA). 2012, 2014, 2015, 2016, 2017, 2018, 2020

IEEE/RAS International Conference on Humanoid Robots (HUMANOIDS). 2016, 2017

IEEE/ASME International Conference on Advanced Intelligent Mechatronics (AIM). 2013

International Conference on Human-Agent Interaction (HAI). 2016

PLoS ONE scientific journal. 2017

## Outreach

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**July 2018.** Laboratory tour at the BRI (ATR): Half-day tour involving presentations and robot demonstrations for 20 visiting Masters students from the University of Ljubljana, Slovenia.

**June 2017.** FB20 Summer Fest (TU Darmstadt): open tour celebrating the new laboratory inauguration with robot demonstrations for the general public.

**August 2016.** Kinderuni Darmstadt (TU Darmstadt): organized interactive sessions using the robot platforms for elementary school students.

**September 2015.** Kinderuni Darmstadt (TU Darmstadt): organized interactive sessions using the robot platforms for elementary school students.

**April 2015.** (TU Darmstadt). Organization of demonstrations for German media.

**March 2015.** (TU Darmstadt). KID Science Radioclub: organized interactive sessions, lab tours, and live demonstrations using the robot platforms.

## Publications

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### Journal Articles

- [1] **Maeda, G.**; Koc, O.; Morimoto, J. (Accepted) "Phase Portraits as Movement Primitives for Fast Humanoid Robot Control". *Neural Networks*.
- [2] Lioutikov, R.; **Maeda, G.**; Veiga, F.; Kersting, K.; Peters, J. (2020) "Learning Attribute Grammars for Movement Primitive Sequencing". *The International Journal of Robotics Research (IJRR)*. vol. 39, no. 1, pp. 21—38.
- [3] Ewerton, M.; Arenz, O.; **Maeda, G.**; Koert, D.; Kolev, Z.; Takahashi, M.; Peters, J. (2019). "Learning Trajectory Distributions for Assisted Teleoperation and Path Planning", *Frontiers*. vol. 6.
- [4] Celemin, C.; **Maeda, G.**; Ruiz-del-Solar, J.; Peters, J.; Kober, J. (2019). "Reinforcement Learning of Motor Skills using Policy Search and Human Corrective Advice", *International Journal of Robotics Research (IJRR)*. vol. 38, no. 14, pp. 1560–1580.
- [5] Koc, O.; **Maeda, G.**; Peters, J. (2019). "Optimizing the Execution of Dynamic Robot Movements with Learning Control". *IEEE Transactions on Robotics (TRO)*. vol. 35 no. 4. pp. 909–924.
- [6] Ewerton, M.; Rother, D.; Weimar, J.; Kollegger, G.; Wiemeyer, J.; Peters, J.; **Maeda, G.** (2018). "Assisting Movement Training and Execution with Visual and Haptic Feedback", *Frontiers in Neurobotics*, vol. 12, pp. 24.
- [7] Koc, O.; **Maeda, G.**; Peters, J. (2018). "Online optimal trajectory generation for robot table tennis", *Robotics and Autonomous Systems (RAS)*, vol. 105, pp.121-137.
- [8] **Maeda, G.**; Ewerton, M; Neumann, G.; Lioutikov, R.; Peters, J. (2017). "Phase Estimation for Fast Action Recognition and Trajectory Generation in Human-Robot Collaboration", *International Journal of Robotics Research (IJRR)*, vol.36, no 13-14, pp. 1579–1594.
- [9] Lioutikov, R.; Neumann, G.; **Maeda, G.**; Peters, J. (2017). "Learning Movement Primitive Libraries through Probabilistic Segmentation", *International Journal of Robotics Research (IJRR)*, vol.36, no 8, pp. 879–894.
- [10] **Maeda, G.**; Ewerton, M; Koert, D.; Peters, J. (2016). "Acquiring and Generalizing the Embodiment Mapping from Human Observations to Robot Skills", *IEEE Robotics and Automation Letters (RA-L)*, vol. 1, no 2, pp. 784–791.

- [11] **Maeda, G.**; Neumann, G.; Ewerton, M.; Lioutikov, R.; Kroemer, O.; Peters, J. (2016). "Probabilistic Movement Primitives for the Recognition and Coordination of Multiple Human-Robot Collaborative Tasks", *Autonomous Robots (AURO)*, vol. 41, no. 3, pp. 593–612.
- [12] **Maeda, G.**; Manchester, I.; Rye, D. (2015). "Combined ILC and disturbance observer for the rejection of near-repetitive disturbances, with application to excavation", *IEEE Transactions on Control Systems Technology*, vol. 23, no. 5, pp. 1754–1769.
- [13] Sato, K.; **Maeda, G.** (2009). "A practical control method for precision motion – Improvement of NCTF control method for continuous motion control", *Precision Engineering*, vol. 33, no. 2, pp. 175–186.
- [14] **Maeda, G.**; Sato, K. (2008). "Practical control method for ultra-precision positioning using a ballscrew mechanism", *Precision Engineering*, vol. 32, no. 4, pp. 309–318.
- [15] Sato, K.; **Maeda, G.** (2008). "Practical ultraprecision positioning of a ball screw mechanism", *International Journal of Precision Engineering and Manufacturing*, vol. 9, no. 2, pp. 44–49.
- [16] **Maeda, G.**; Sato, K.; Hashizume, H.; Shinshi, T. (2006). "Control of an XY nano-positioning table for a compact nano-machine tool", *JSME International Journal Series C*, vol. 49, no. 1, pp. 21–27.

#### Book Chapter

- [1] Lioutikov, R.; Kroemer, O.; Peters, J.; **Maeda, G.** (2016). "Learning Manipulation by Sequencing Motor Primitives with a Two-Armed Robot", *Advances in Intelligent Systems and Computing. Proceedings of the 13th International Conference on Intelligent Autonomous Systems (IAS)*, pp. 1601–1611.
- [2] **Maeda, G.**; Rye, D.; Singh, S. (2014). "Iterative autonomous excavation", In *Field and Service Robotics, Series: Springer Tracts in Advanced Robotics*, pp. 369–382.

#### Peer-Reviewed Conference Articles

- [1] Ewerton, M.; **Maeda, G.**; Koert, D.; Kolev, Z.; Takahashi, M.; Peters, J. (2019). "Reinforcement learning of trajectory distributions: Applications in assisted teleoperation and motion planning". *Proceedings of the IEEE/RSJ Conference on Intelligent Robots and Systems (IROS)*
- [2] **Maeda, G.**; Koc, O.; Morimoto, J. (2018). "Reinforcement Learning of Phase Oscillators for Fast Adaptation to Moving Targets", *Conference on Robot Learning (CoRL)*.
- [3] Lioutikov, R.; **Maeda, G.**; Veiga, F.; Kersting, K.; Peters, J. (2018). "Inducing Probabilistic Context-Free Grammars for the Sequencing of Robot Movement Primitives", *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*.
- [4] Koert, D.; **Maeda, G.**; Neumann, G.; Peters, J. (2018). "Learning Coupled Forward-Inverse Models with Combined Prediction Errors", *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*.
- [5] **Maeda, G.**; Ewerton, M.; Osa, T.; Busch, B.; Peters, J. (2017). "Active Incremental Learning of Robot Movement Primitives", *Proceedings of Machine Learning Research (PMLR): Conference on Robot Learning (CoRL)*, vol. 78, pp. 37–46.
- [6] Busch, B.; **Maeda, G.**; Mollard, Y.; Demangeat, M.; Lopes, M. (2017). "Postural Optimization for an Ergonomic Human-Robot Interaction", *Proceedings of the IEEE/RSJ Conference on Intelligent Robots and Systems (IROS)*.
- [7] **Maeda, G.**; Maloo, A.; Ewerton, M.; Lioutikov, R.; Peters, J. (2016). "Anticipative Interaction Primitives for Human-Robot Collaboration", *AAAI Fall Symposium Series. Shared Autonomy in Research and Practice*, Arlington, VA, USA.
- [8] Koc, O.; **Maeda, G.**; Peters, J. (2016). "A New Trajectory Generation Framework in Robotic Table Tennis", *Proceedings of the IEEE/RSJ Conference on Intelligent Robots and Systems (IROS)*, pp. 3750–3756.

- [9] Ewerton, M.; **Maeda, G.**; Neumann, G.; Kisner, V.; Kollegger, G.; Wiemeyer, J.; Peters, J. (2016). "Movement Primitives with Multiple Phase Parameters", *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, pp. 201–206.
- [10] Koc, O.; **Maeda, G.**; Neumann, G.; Peters, J. (2015). "Optimizing Robot Striking Movement Primitives with Iterative Learning Control", *Proceedings of the International Conference on Humanoid Robots (HUMANOIDS)*, pp. 80–87.
- [11] Lioutikov, R.; Neumann, G.; **Maeda, G.**; Peters, J. (2015). "Probabilistic Segmentation Applied to an Assembly Task", *Proceedings of the International Conference on Humanoid Robots (HUMANOIDS)*, pp. 533–540
- [12] **Maeda, G.**; Neumann, G.; Ewerton, M.; Lioutikov, R.; Peters, J. (2015). "A Probabilistic Framework for Semi-Autonomous Robots Based on Interaction Primitives with Phase Estimation", *International Symposium of Robotics Research (ISRR)*
- [13] Ewerton, M.; **Maeda, G.**; Peters, J.; Neumann, G. (2015). "Learning Motor Skills from Partially Observed Movements Executed at Different Speeds", *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pp. 456–463
- [14] Ewerton, M.; Neumann, G.; Lioutikov, R.; Ben Amor, H.; Peters, J.; **Maeda, G.** (2015). "Learning Multiple Collaborative Tasks with a Mixture of Interaction Primitives", *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, pp. 1535–1542.
- [15] **Maeda, G.**; Ewerton, M.; Lioutikov, R.; Ben Amor, H.; Peters, J.; Neumann, G. (2014). "Learning Interaction for Collaborative Tasks with Probabilistic Movement Primitives", *Proceedings of the International Conference on Humanoid Robots (HUMANOIDS)*, pp. 527–534
- [16] **Maeda, G.**; Rye, D. (2012). "Learning disturbances in autonomous excavation", in *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pp. 2599–2605.
- [17] **Maeda, G.**; Rye, D.; Singh, S. (2012). "Iterative autonomous excavation", in *The 8th International Conference on Field and Service Robotics (FSR)*.
- [18] **Maeda, G.**; Singh, S.; Rye, D. (2011). "Improving operational space control of heavy manipulators via open-loop compensation", in *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pp. 725–731.
- [19] **Maeda, G.**; Singh, S.; Durrant-Whyte, H. (2011). "A tuned approach to feedback motion planning with RRT's under model uncertainty", in *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, pp. 2288–2294.
- [20] **Maeda, G.**; Singh, S.; Durrant-Whyte, H. (2010). "Feedback motion planning approach for nonlinear control using gain scheduled RRT's", in *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pp. 119–126.
- [21] Sato, K.; **Maeda, G.** (2007). "Simple and practical control method for ultra-precision positioning: Application to a ballscrew mechanism", in *Proc. of ASPE Annual Meeting*, pp. 179–182.

#### Workshop and Poster Presentations

- [1] Zhangwei H, Nagarajan P, **Maeda G.** "Swarm-inspired Reinforcement Learning via Collaborative Inter-agent Knowledge Distillation". *NeurIPS 2019 Deep reinforcement Learning Workshop*. 2019.
- [2] **Maeda, G.**; Morimoto, J. (2018). "Acquisition and Coordination of Motor Skills from Human Observations", *Workshop on Artificial Intelligence and Brain Science*. Okinawa Institute of Science and Technology.
- [3] Celemin, C.; **Maeda, G.**; Kober, J.; Ruiz-del-Solar, J. (2017). "Human Corrective Advice in the Policy Search Loop", *Workshop: Human-in-the-loop robotic manipulation: on the influence of the human role (IROS)*.



- [4] Ewerton, M.; **Maeda, G.**; Rother, D.; Weimar, J.; Lotter, L.; Kollegger, G.; Wiemeyer, J.; Peters, J. (2017). "Assisting the practice of motor skills by humans with a probability distribution over trajectories", *Workshop: Human-in-the-loop robotic manipulation: on the influence of the human role (IROS)*.
- [5] Ewerton, M.; Kollegger, G.; **Maeda, G.**; Wiemeyer, J.; Peters, J. (2017). "Iterative Feedback-basierte Korrekturstrategien", *Workshop: beim Bewegungslernen von Mensch-Roboter-Dyaden, DVS Sportmotorik 2017*.
- [6] **Maeda, G.**; Maloo, A.; Ewerton, M.; Lioutikov, R.; Peters, J. (2016). "Proactive Human-Robot Collaboration with Interaction Primitives", *International Workshop on Human-Friendly Robotics (HFR)*, Genoa, Italy.

### Supervised Theses

- [1] Maghrabi, A. (2019). "A Mobile Humanoid Basketball Player: Mixing Primitive Skills via SLAM", Master Thesis, Supervised with Morimoto, J; (ATR) and Ijspeert, A (EPFL).
- [2] Koc, O. (2018). "Optimal Trajectory Generation and Learning Control for Robot Table Tennis", PhD Thesis, TU Darmstadt. As co-supervisor, with Jan Peters as main supervisor.
- [3] Lioutikov, R. (2018). "Parsing Motion and Composing Behavior for Semi-Autonomous Manipulation", PhD Thesis, TU Darmstadt. As co-supervisor, with Jan Peters as main supervisor.
- [4] Lolkes, C. (2017). "Incremental Imitation Learning with Estimation of Uncertainty", Bachelor Thesis, TU Darmstadt.
- [5] Koert, D. (2016). "Combining Human Demonstrations and Motion Planning for Movement Primitive Optimization", Master Thesis, TU Darmstadt.
- [6] Alte, D. (2016). "Control of a robotic arm using a low-cost BCI", Bachelor Thesis, TU Darmstadt.
- [7] Koert, D. (2015). "Inverse Kinematics for Optimal Human-Robot Collaboration", Honors Thesis, TU Darmstadt.
- [8] Ewerton, M. (2014). "Modeling Human-Robot Interaction with Probabilistic Movement Representations", Master Thesis, TU Darmstadt.

### Patents

- [1] Suzuki, S.; **Maeda, G.** "Offset printing method and apparatus" 2012, US Patent 13/265,653.
- [2] Suzuki, S.; **Maeda, G.** "Inking method and apparatus thereof" 2011, US Patent 13/061,585.