

# Feature Set Refinement for Robotic Tasks by Human Demonstration

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**Abstract**—Feature selection is an essential part of representing the task in robot learning. With a relevant set of features, the robot can not only have a better performance but also decrease the learning cost. In this work, the feature selection method is proposed to help the robot determine which subset of the features is relevant to represent a task. We implement an experiment system for human-robot interaction in simple task as proofing our concept as well as showing the preliminary results

Keywords: Human-Robot Interaction, Feature Selection

## I. INTRODUCTION

Transferring knowledge is defined as allowing the instructor to share or disseminate the knowledge or experiment to the learner. In robotic field, Human-Robot knowledge transfer which allows non-robotic-experts have opportunities to interact with robots is one of the areas that attracts attention of many researchers. There are two parts in Human-Robot knowledge transfer. The first part is human-to-robot part in which robot learn the knowledge from human through human instruction and the other part is robot-to-human part where robot teach the task to human [1].

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TABLE I  
AN EXAMPLE OF A TABLE

One	Two
Three	Four

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Fig. 1. Inductance of oscillation winding on amorphous magnetic core versus DC bias magnetic field

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#### V. CONCLUSIONS

A conclusion section is not required. Although a conclusion may review the main points of the paper, do not replicate the abstract as the conclusion. A conclusion might elaborate on the importance of the work or suggest applications and extensions.

## APPENDIX

Appendixes should appear before the acknowledgment.

### ACKNOWLEDGMENT

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