* **Autonomous Vehicle Perception: The technology of today and tomorrow, Van Brummelen and al.**
* Review of state-of-the-art techniques in localization, mapping, and AV vision.
* Lots of interesting references on direct perception approach and behavior reflex see section 4.4
* **Imitation learning by Mykel**

Policy = a neural net that takes s as input and splits out distribution over a.

Global objective : find the best set of params so that (a|s) best mimics (a|s)

Two ways to train :

1. Using BC (behavioral cloning) : you basically train the network using classic regression so that actions spit by match actions spit in similar conditions. Performance of the policy is then evaluated on its ability to reproduce expert-like actions. The dataset is seen labeled in the sense (x,y) = (s,)
2. Using RL :