

(3) learning happens only when CoS of all three roles are filled and the desire to learn is present

This implies that actions that are not about objects can't be learned currently

(8) one can also imagine having a bit more complex actions at this level. In the motor part, each action will then trigger different configuration of preconditions of EBs

(7) In our case, grasp can happen after reaching as we are just using magnets. In real case, we would need to first open the gripper

(6) it would make more sense if reach take the height axis also into account, but I don't know whether one can extract this information from camera

(2) attention select objects that are getting closer to the hand

(1) distinction between tool and target objects are made by checking whether the object is moving  
should be possible  
using two fields with different time scale?

Scenario: (hand, knife, reach), (hand, knife, grasp), (knife, apple, reach), (knife, apple, cut)... (hand, knife, detach), (hand, apple, grasp)...

