**What Have I been working on**

Skill learning methods

* Imitation Learning
  + BC
    - HMM\*
    - DMP
    - PRoMP
    - SEDS\*
    - GMM
    - GMR
    - GPR
    - LWPR
  + Inverse RL
    - Max Margin\*
    - Max Entropy\*
    - Feature Maxin \*
    - Relative Entropy\*
* RL
  + Value-function
  + Policy-function

Question

* Imitation learning: Model-based vs. Model free
  + Is model-based only regression?
  + And model free more methods like DMP/PRoMP
* IRL: Model-based vs Model free
  + How to determine the difference?
* How to determine if a method is online
  + My interpretation:
    - online learning if the policy is being updated while the expert is performing the demonstrations
    - is offline if the experts first does a demonstration and next, based on this obtained data, a policy is computed
  + Answer:  
    Online is final behaviour is not same as initial behaviour
    - Two classes
      * Continuous: learning is not interrupted
      * Discrete: step by step/ per iterations/ per demonstrations
* Trying to find information about continuous skill learning
  + What is relevant
  + How to include it?
  + How to divide the chapter?
    - Per task?
    - Per method?
  + How to compare?
  + NOTE: ALSO FOUND BENCHMARKS, IS THIS RELEVANT?
  + **TIPS**
    - **Use videos!**
      * **Especially RL is useful**
    - Examples:
      * Human-Like Adaptation of Force and Impedance in Stable and Unstable Interactions – Yang 2011  
        <https://ieeexplore.ieee.org/abstract/document/5940238?casa_token=4vkwAKGV_yMAAAAA:OBMf-kmE5-9xUIjcjTlMN27jc-aw4Dq9Jd1Y9gsPRzkJEE8FxgIKdJswqeXayhUZG9qXuH7Yg9U>
      * Gams 2016 – DMP  
        Adaptation and coaching of periodic motion primitives through physical and visual interaction
      * Gams 2014 – ILC  
        Coupling Movement Primitives: Interaction With the Environment and Bimanual Tasks
      * Abud-daka
        + Force-based variable impedance learning for robotic manipulation
        + Solving peg-in-hole tasks by human demonstration and exception strategies
        + Adaptation of manipulation skills in physical contact with the environment to reference force profiles
    - Focus more on task/changes – Different changes of the skill
      * Stiffness/motion/force/torque
        + Torque – exoskeleton
        + Have one of each now above!
      * Add one of RL

How does it work with handing in the literature

* Does not matter if I delay

Include it in definition you can

* RL – Online
  + Define it yourself (in introduction)
* Policies changes so you can say
  + Discountinous
* Continous learning
  + Try to explain the essence
    - Of the experiments
  + Try to have a figure per experiment
* For explaining a method
  + RL
    - Make it more of a story
    - For example learning a game
  + Maybe add some figures here as well?
    - E.g. the RL example

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* Can you schedule half an hour with David Abbink and Luka a soon as possible
* Have to make a presentation for him what I am working on
  + Topic
  + Research question
  + How to structure
  + Go a bit into
* Don’t underestimated the discussion + conclusion
  + Conclusion 2/3 paragraphs
* Tries to summarize the

Points of David

* Adding a summary at the end of a chapter