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Learning human behaviors from motion capture

by adversarial imitation

Josh Merel, Yuval Tassa, Dhruva TB, Sriram Srinivasan, Jay Lemmon, Ziyu Wang,

Greg Wayne, Nicolas Heess

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Rapid progress in deep reinforcement learning has made it increasingly feasible

to train controllers for high-dimensional humanoid bodies. However, methods that use pure reinforcement learning with simple reward functions tend to pro-

duce non-humanlike and overly stereotyped movement behaviors. In this work, we extend generative adversarial imitation learning to enable training of generic

neural network policies to produce humanlike movement patterns from limited demonstrations consisting only of partially observed state features, without access

to actions, even when the demonstrations come from a body with different and unknown physical parameters. We leverage this approach to build sub-skill policies

from motion capture data and show that they can be reused to solve tasks when controlled by a higher level controller. [video abstract]

The problem of building a programmable humanoid dates back centuries. In 1495, five years after drawing the Vitruvian Man, Leonardo da Vinci constructed a humanoid automaton in the form of

an armored knight [I]. The knight was able to wave, sit up, and open and close its jaw via power delivered by a crank. Unlike most clockwork automata, which could only produce movements

注释

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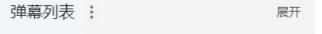
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(1) 论文题目: Learning human behaviors from motion capture by adversarial imitation (地

(2) 作者: Josh Merel, Yaval Tassa, Dhruva TB, Sriram Srinivasan et al.





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