

Motivation:

- Robots should adapt their behavior to user's specifications.
- Common users may be unable or unwilling to program a robot in the traditional manner.
- Robotic lifelong learning from demonstration can enable users to teach robots to perform new tasks.



```
///  
Private Function ParseRefs(text As String) As String  
Dim a() As String, i As Long, tmpRefs As String, tmpText As String  
a() = Split(text, "<ref>")  
For i = 0 To UBound(a())  
If i = 0 Then  
tmpText = tmpText & a(i)  
Else  
If InStr(a(i), "</ref>") = 0 Then  
tmpText = tmpText & "<big<font color='red'><b>&lt;ref> not closed" & _  
"</b></font></big>" & a(i)  
Else  
tmpRefs = tmpRefs & "#" & getL(a(i), "</ref>") & vbCrLf  
tmpText = tmpText & "<sup>[" & i & "]"</sup>" & getR(a(i), "</ref>")  
End If  
End If  
Next i  
tmpText = Replace(tmpText, "<references/>", tmpRefs) '/// Yes, I know that isn't the  
tmpText = Replace(tmpText, "<references />", tmpRefs) '/// "right" way....  
tmpText = Replace(tmpText, "<references>", tmpRefs)  
ParseRefs = tmpText  
End Function
```

VS



Learning Robot Soccer Skills from Demonstration

Dan Grollman and Chad Jenkins
Robotics, Learning and Autonomy at Brown

ICDL 2007
July 11th, 2007

Used human-mediated demonstration to teach robotic dogs basic soccer skills.

- Walk & Trap
- Seek & Acquire

Task is “unknown” and learned via supervised regression.

- LWPR & SOGP

Techniques are not tied to platforms, demonstrators or learning algorithms.





Users demonstrating robot soccer via wiimote teleoperation

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