

Zi Wang (MIT CSAIL)

Robot Learning





Activve selectiois data efficient



randomly chosen

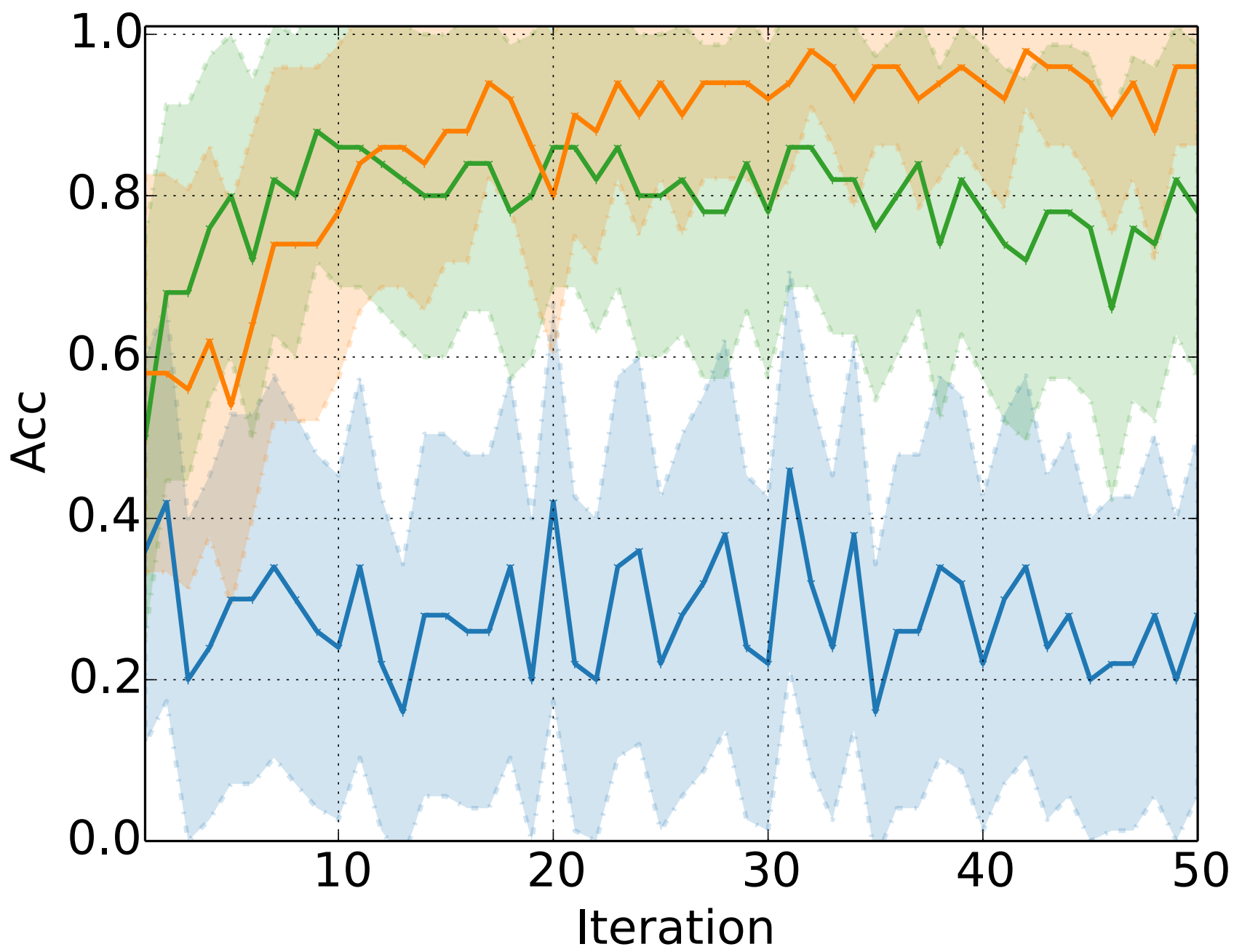
 neural network classifier*

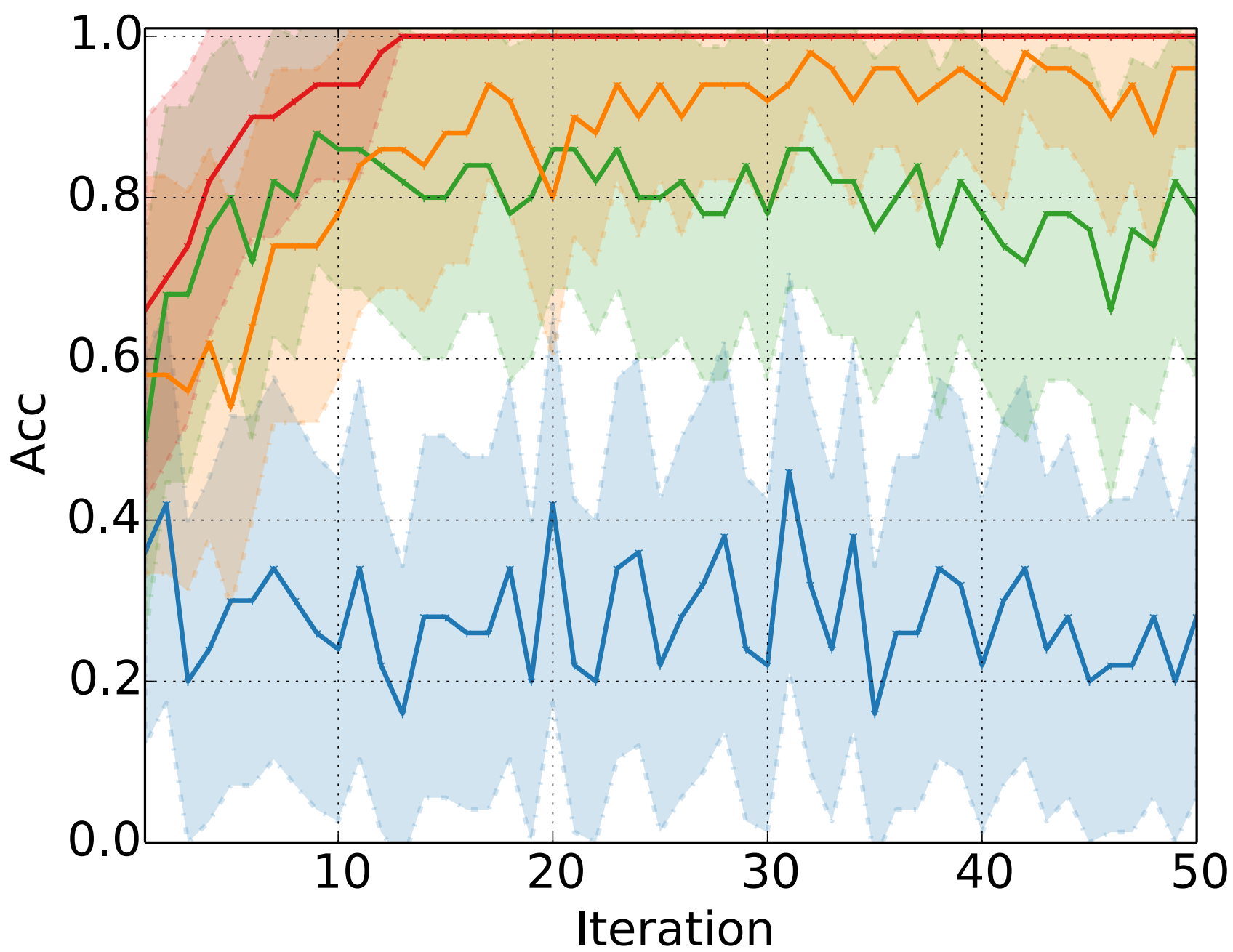
 neural network regression*



GP active learning

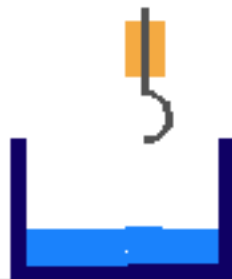
Success rate of recommended 'scop'





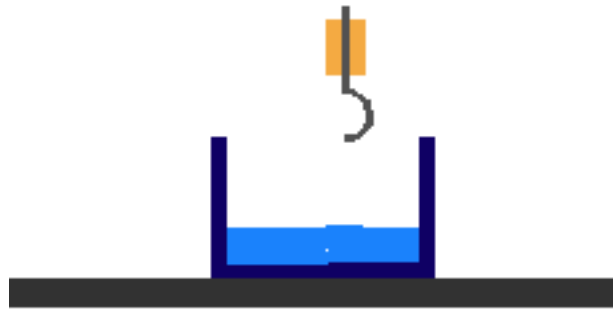
#Training examples

[Kaelbling & Lozano-Perez, ICRA 2017]

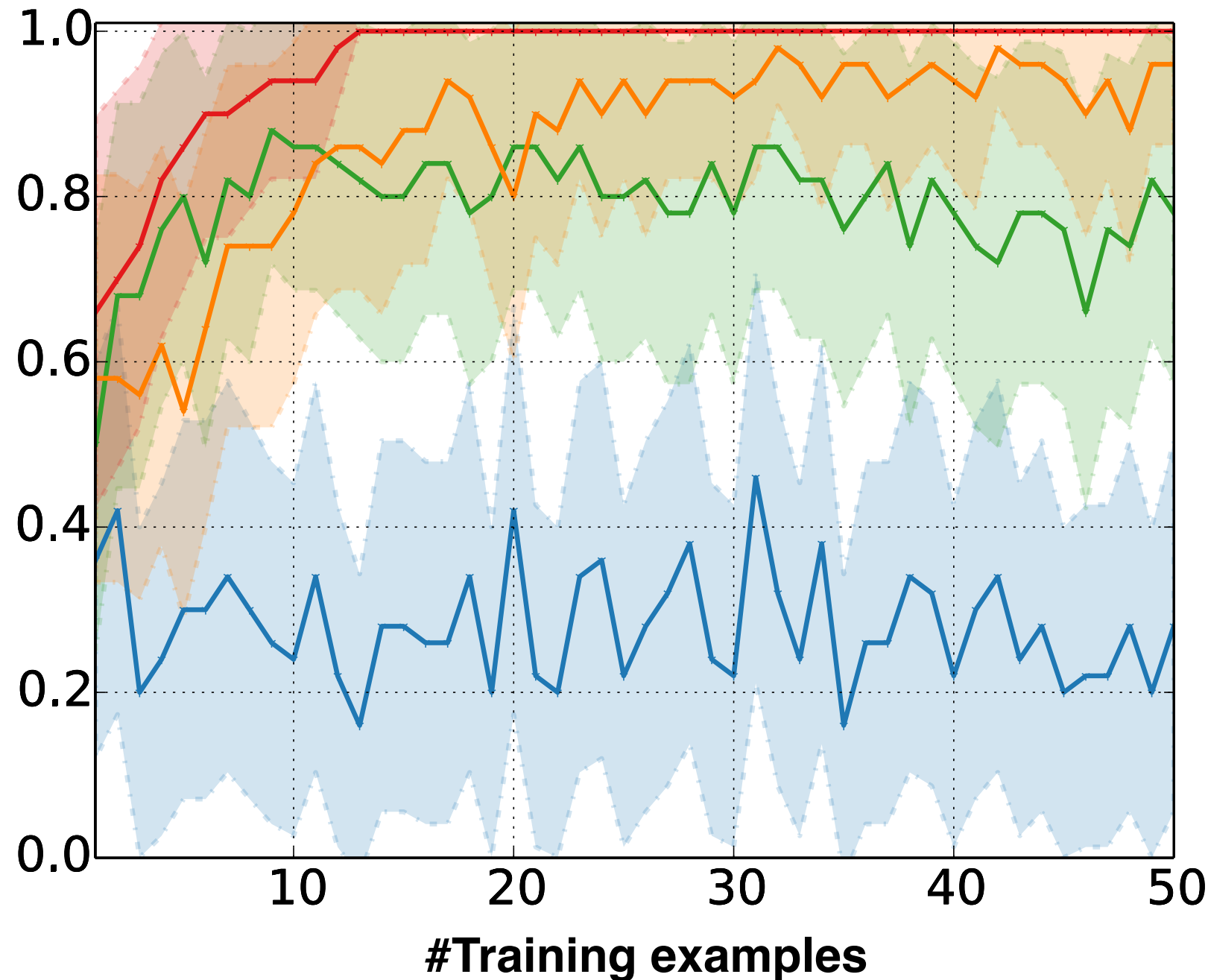


Active selection is data efficient

Success rate of recommended 'scoop'

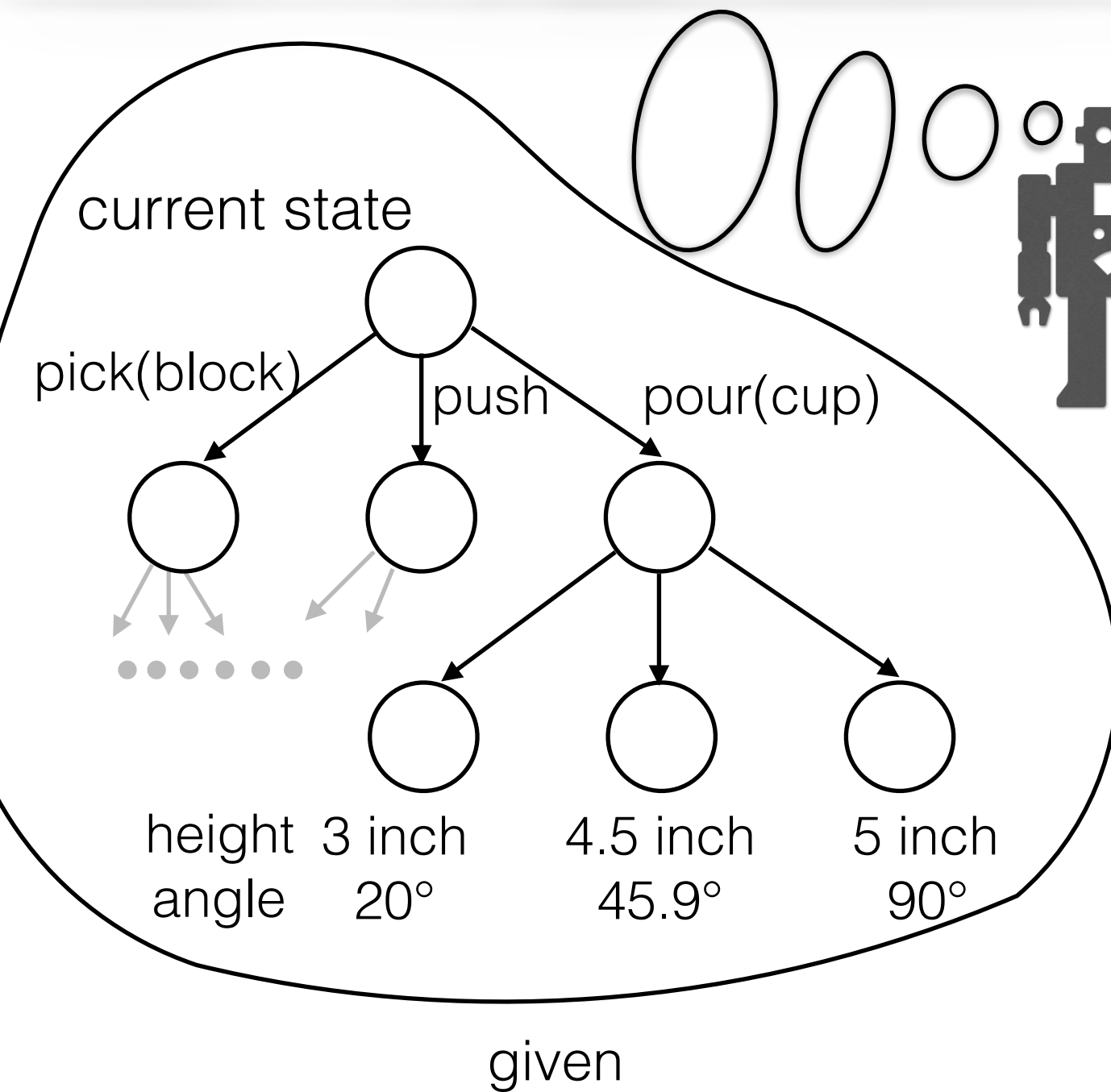


- randomly chosen
- neural network classifier*
- neural network regression*
- GP active learning



[Kaelbling&Lozano-Perez, ICRA 2017]

Use learned models of constraints in TAMP



GoodPour($w_s, h_s, w_t, h_t, c_{grasp}, c_{pour}, r_{pose}$)

