

Zi Wang (MIT CSAIL)

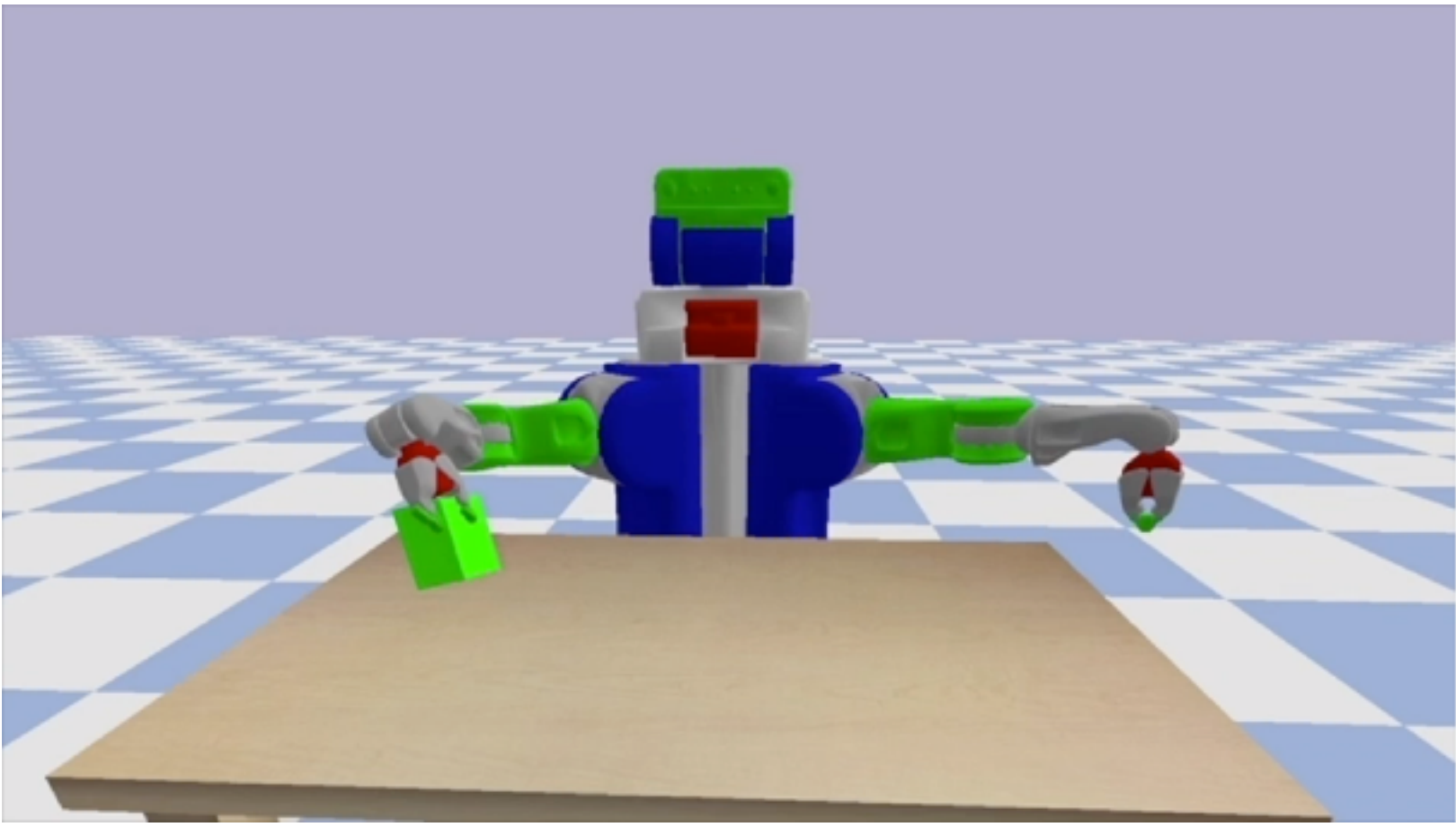
Robot Learning

3

4



Learning from simulation and real world



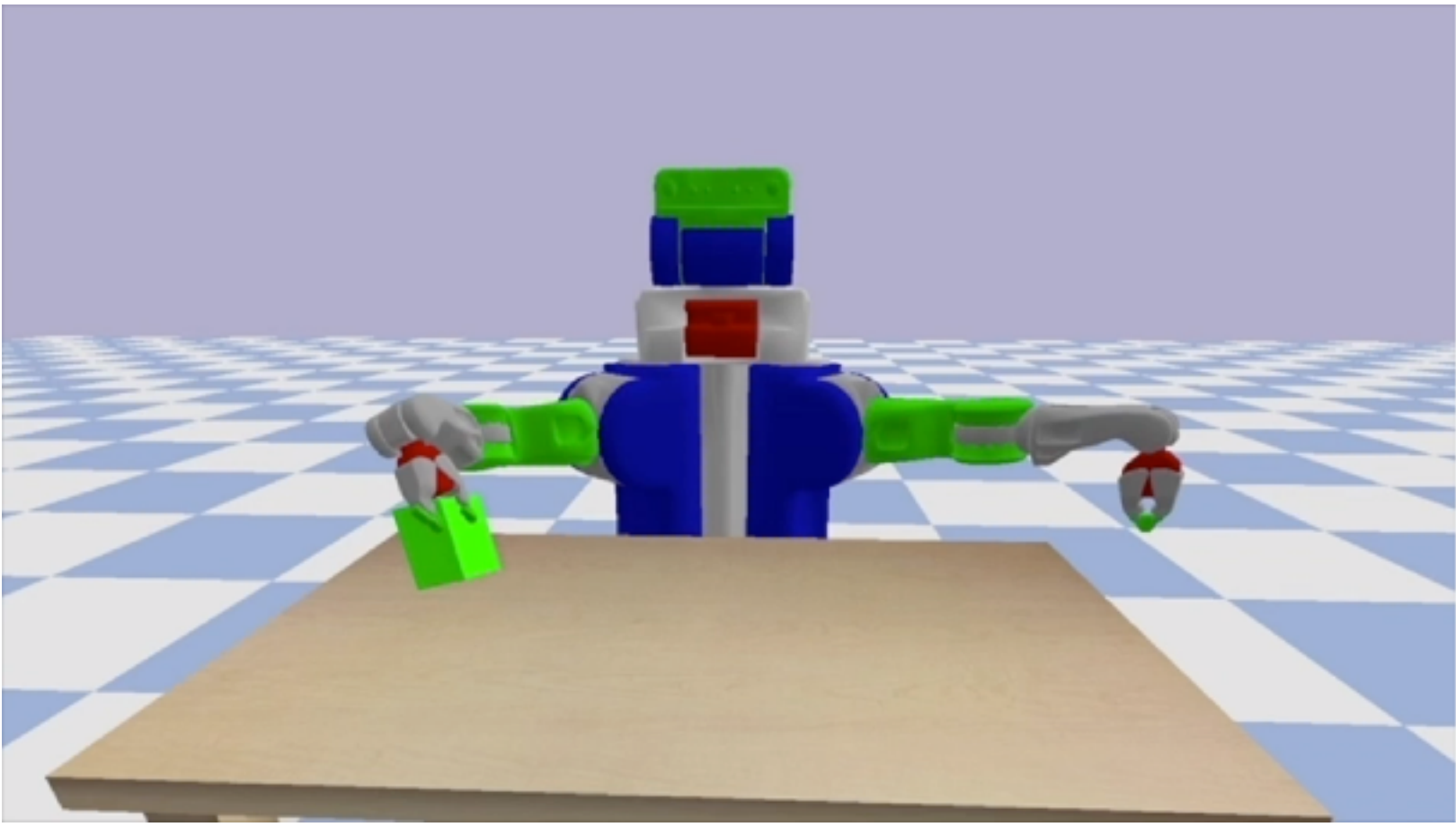
Adaptive transfer kernel weights them appropriately

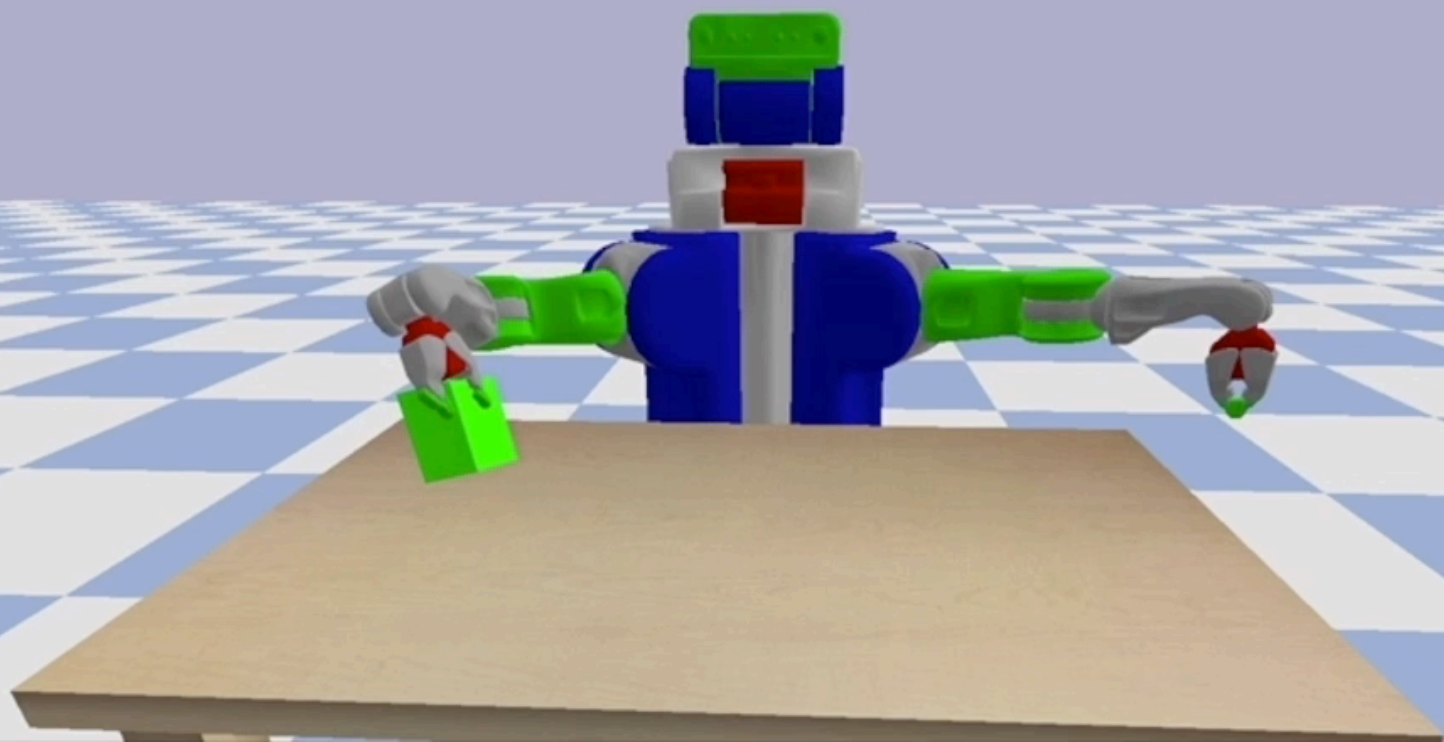
Parameters:

- gripper initial and final y displacement from block
- gripper displacement from block center in z
- gripper opening width
- wrist tilt angle

Objective does not

include orientation



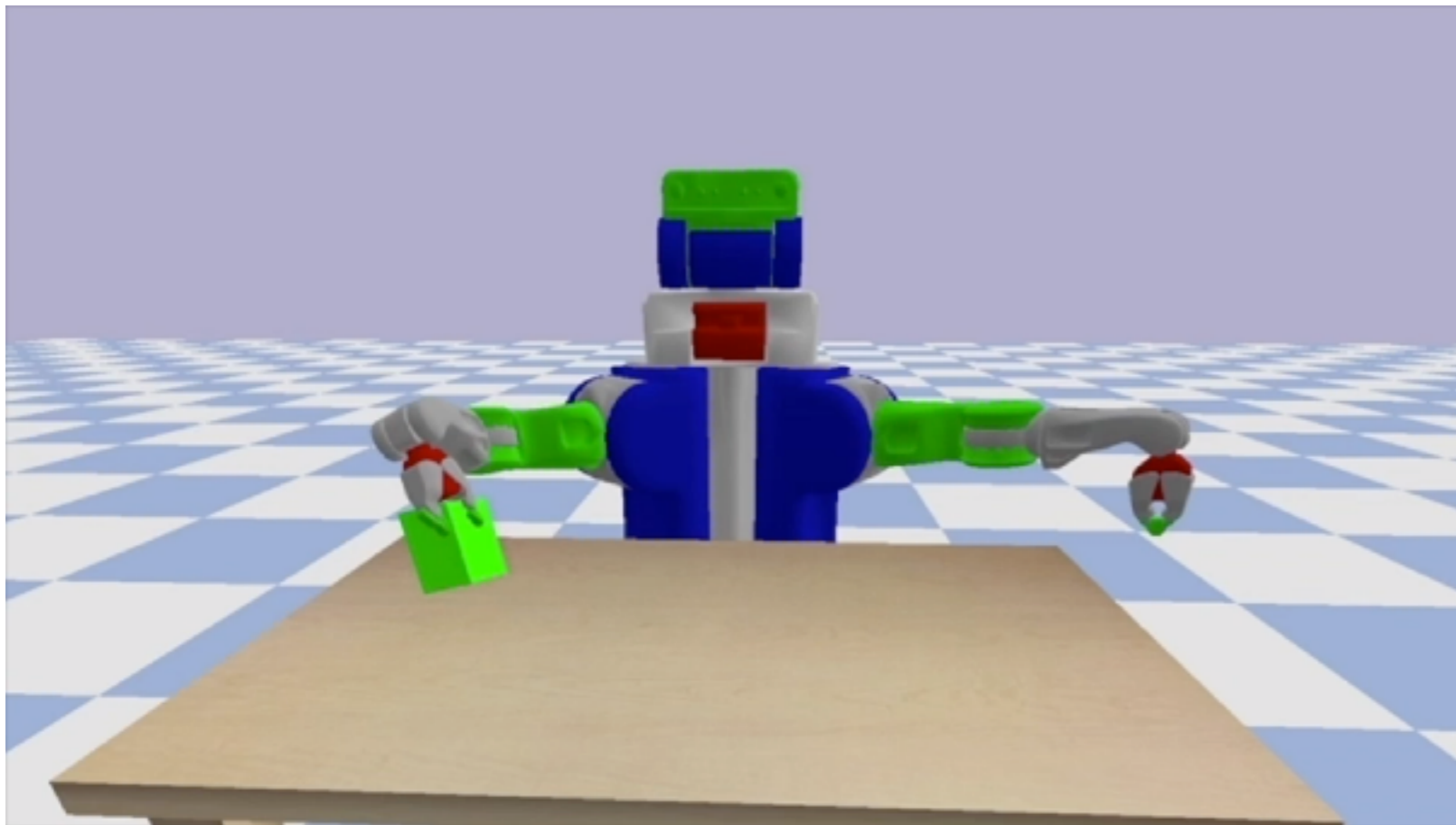


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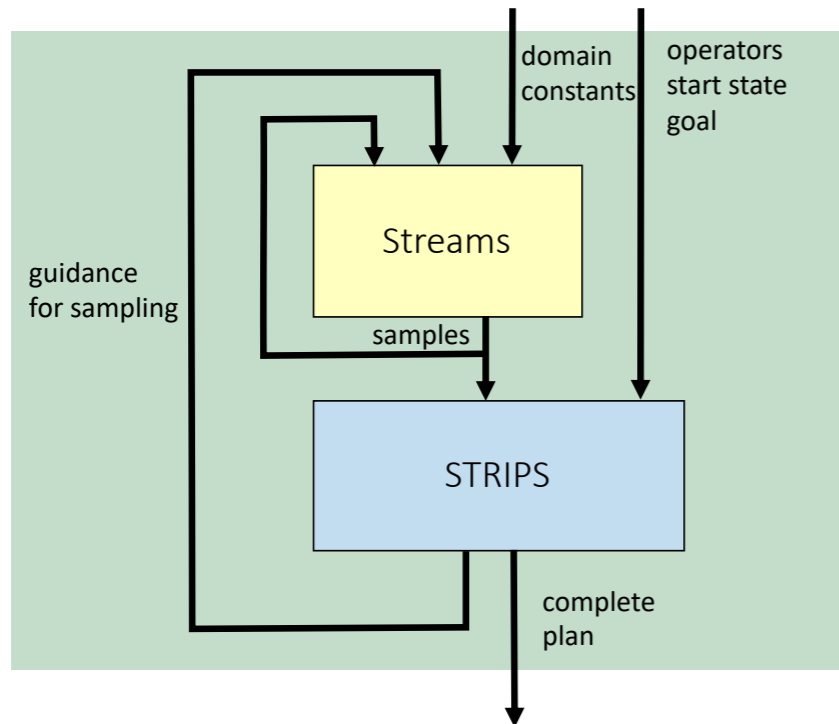
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Planning with Stripstream in hybrid spaces

[Garrett, Lozano-Perez, Kaelbling, RSS 2017]



- Iterative sample-based reduction to STRIPS
- Can use any PDDL planner implementation without modification
 - Incrementally increase universe via sampling in appropriate spaces

- potentially infinite samples
- may be conditioned on a discrete or continuous typed input value
- constraint guaranteed to hold between input and output

