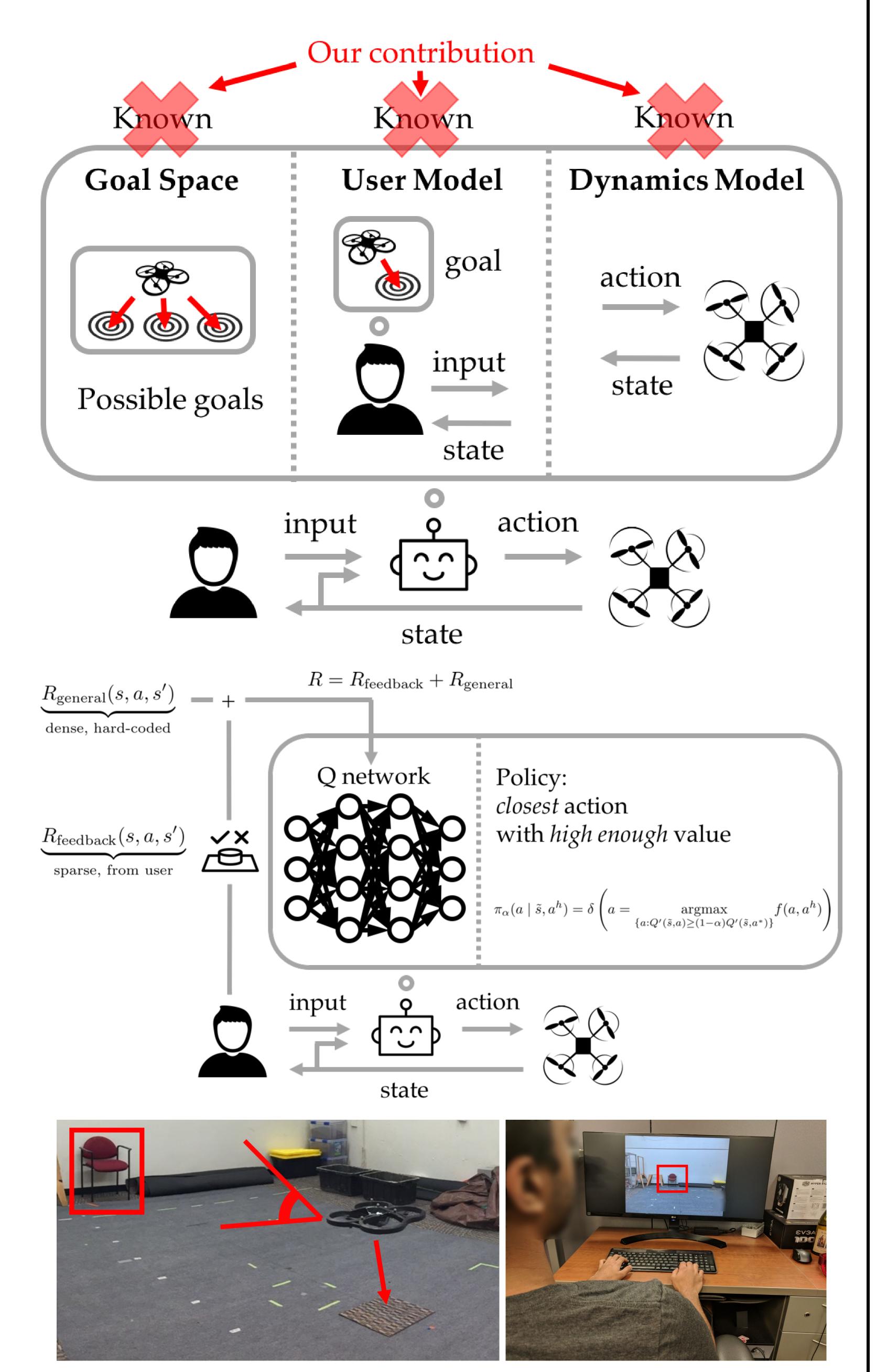
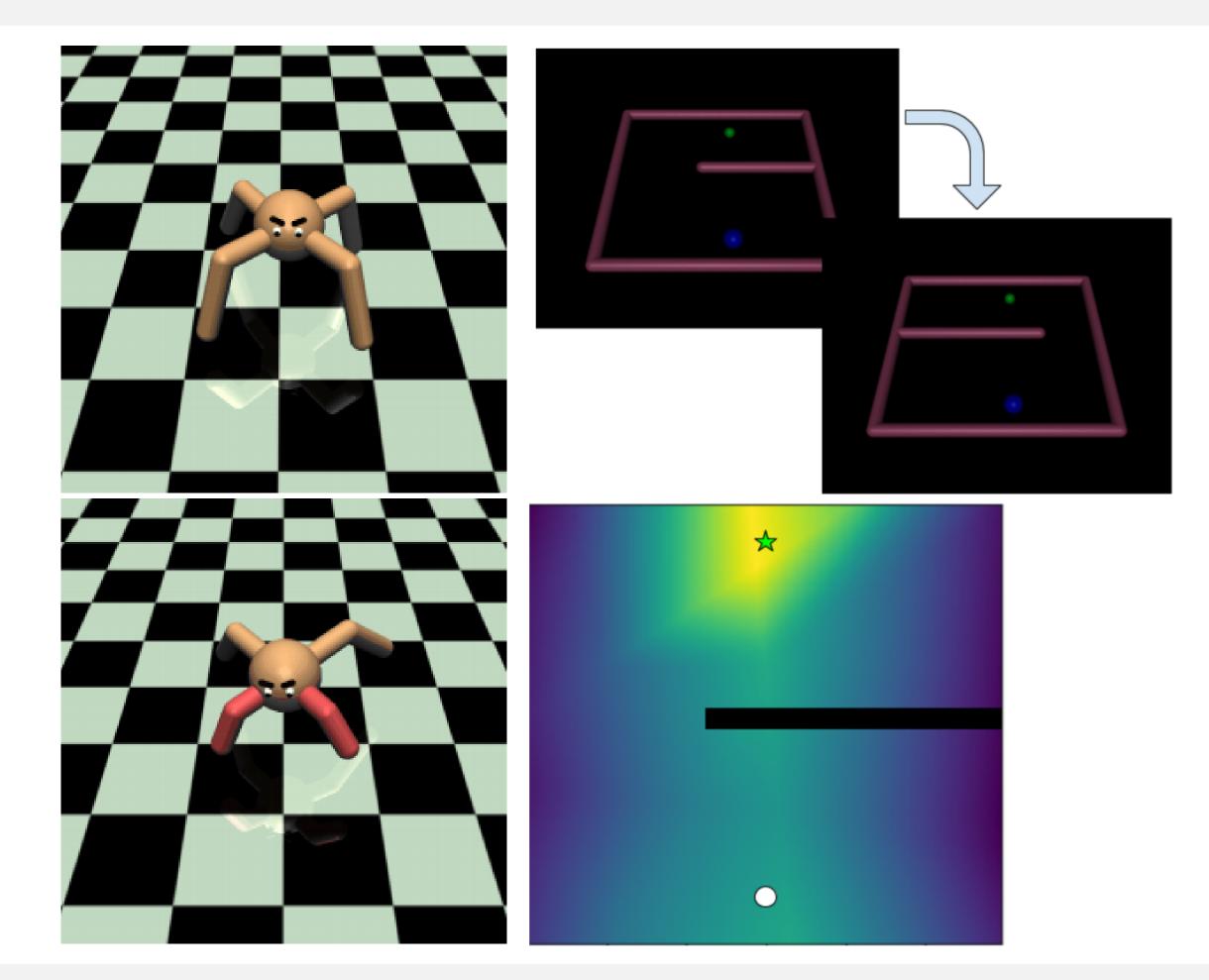
Learning Deep Sensorimotor Policies for Shared Autonomy Sergey Levine, UC Berkeley



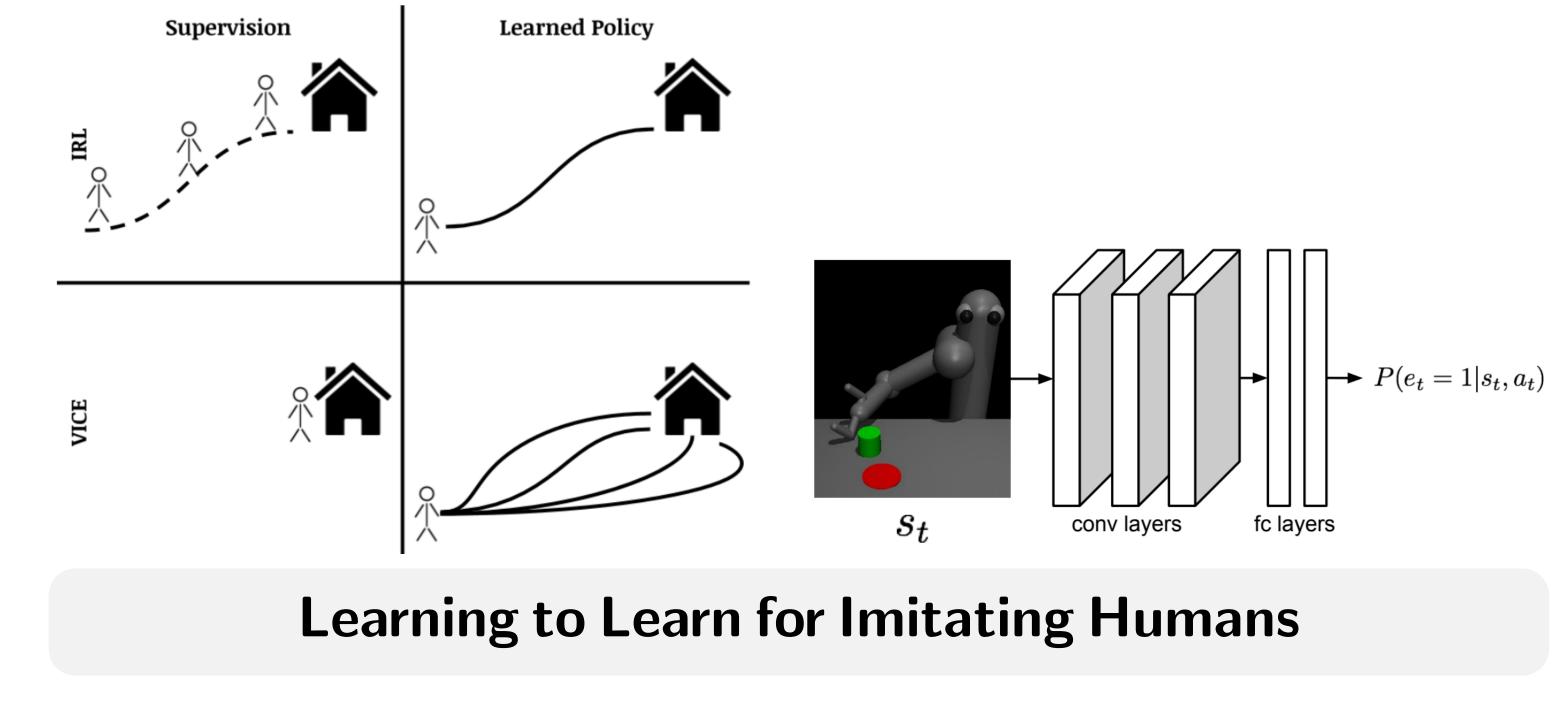
Augmenting Human Control with Deep Q-Learning



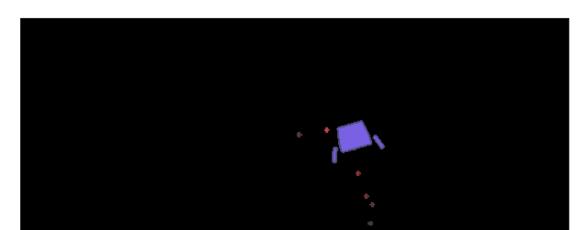
Robust Inverse Reinforcement Learning

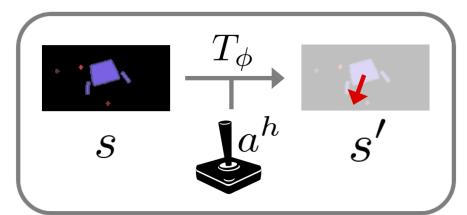


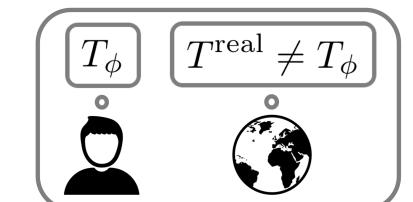
Event-Based Task Specification and Control



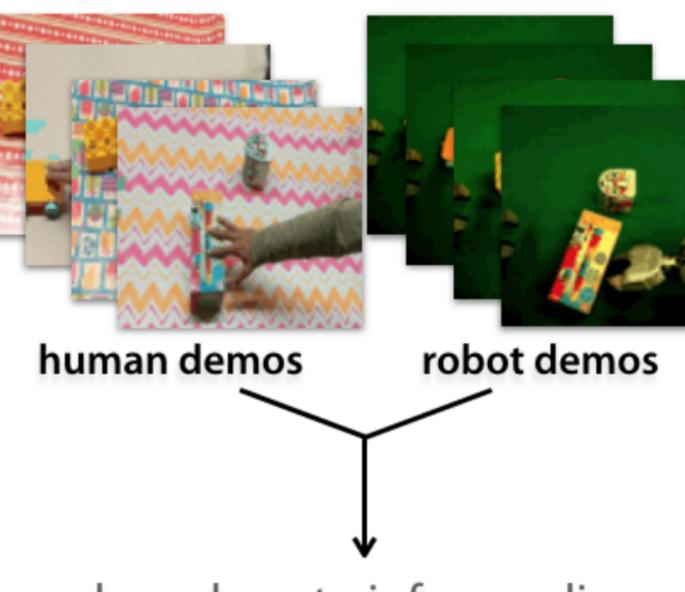
Inferring Beliefs about Dynamics from Behavior







Domain-Adaptive Meta-Learning provide demonstration data pro

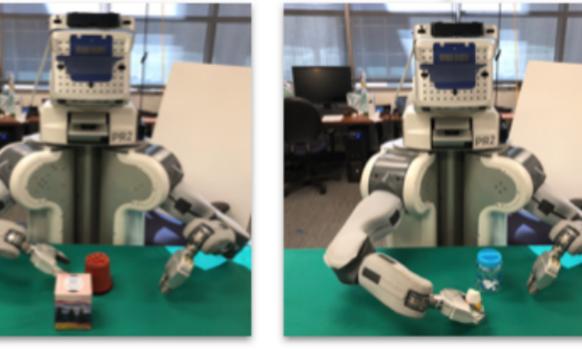


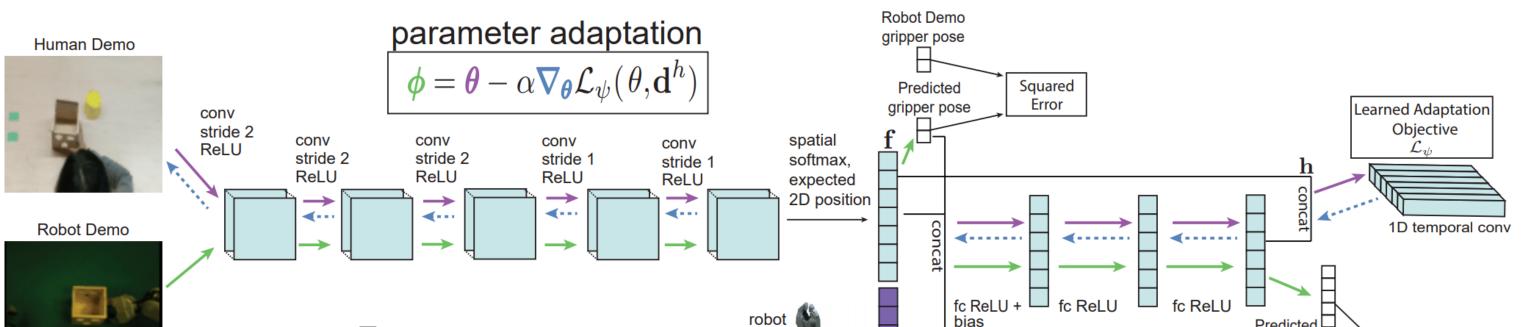
<u>Deployment</u> provide one video of human

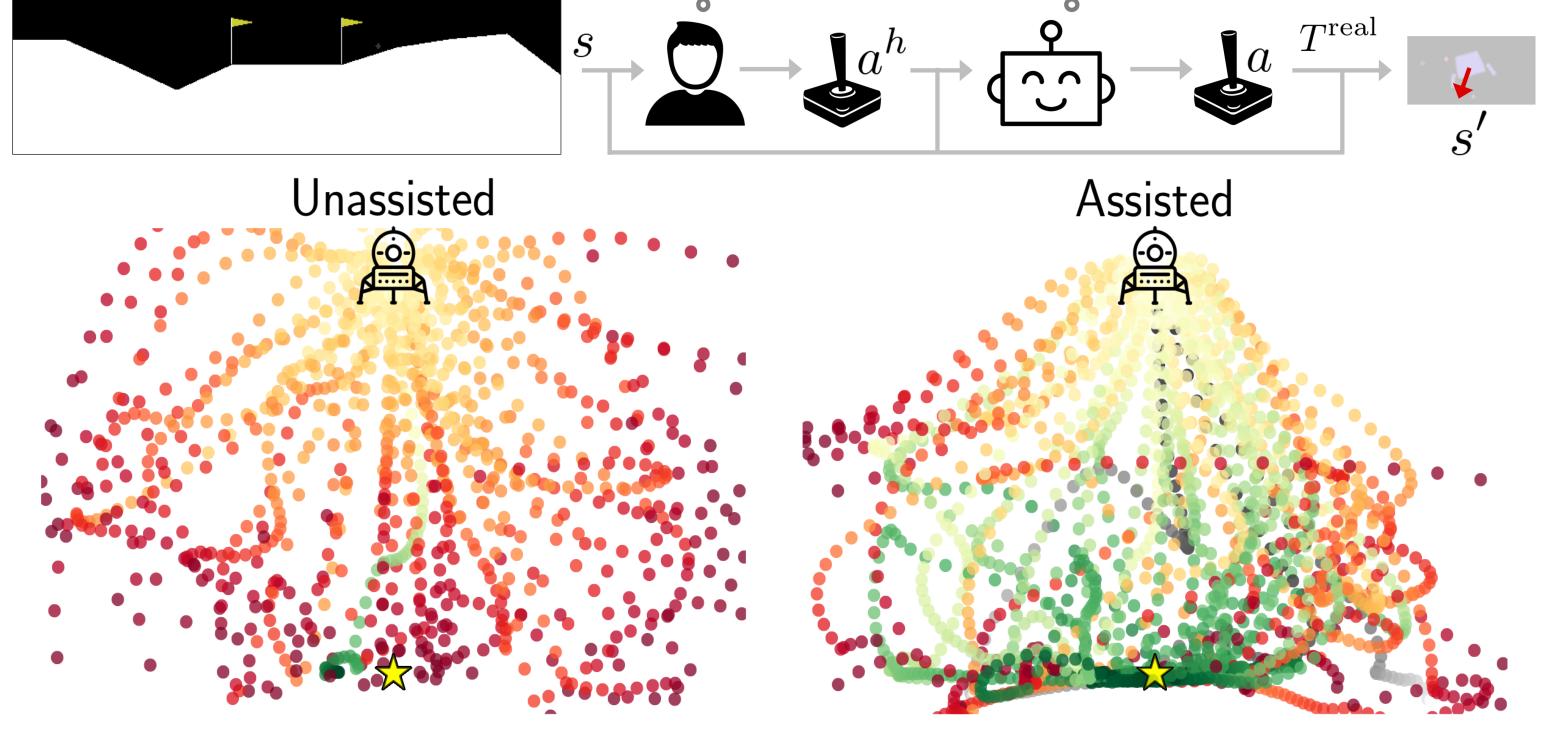


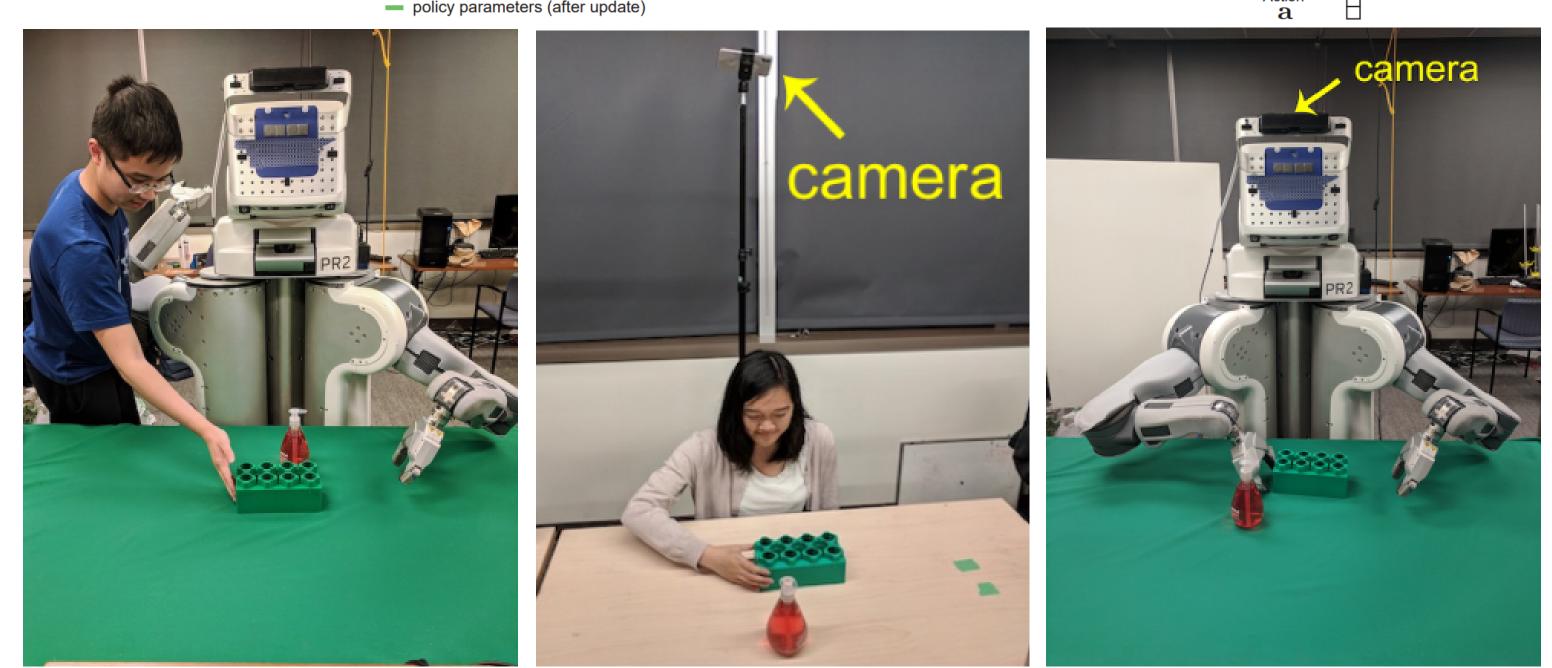




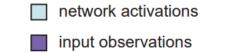








Short Talk during Session 5 (1:30-3pm on Tuesday)



policy parameters (before update)

gradient (for parameter update)



