Fiche developed in the frame of	TYPE:		AREA:
	Conference	Training	**Robotics**, **autonomous systems, artificial intelligence**
	European, national, regional **project**	University course Postgraduate studies	C4ISTAR : command, control, communications, computers, information/intelligence, surveillance
	Policy	Journal	Cybersecurity

Title:

Robot skill learning: imitation, exploitation and control (ROBOT SL)

Description	This project aims to develop an imitation learning framework for robot skill learning and optimization, aiming at endowing robots with versatile skills and thus allowing robots to work in broad application domains.
Goal	This project will provide the first solution for the problem of imitation learning with various constraints (including linear and non-linear, convex and non-convex constraints) and a novel concept of semi-imitation learning by exploring environmental priors. Moreover, it will provide a solution to multi-modal imitation learning from few demonstrations, which can be readily combined with constrained learning and environmental priors. In addition, from a control perspective, this project will study a new concept of control-inspired imitation learning to mimic both human skills and human reactions under perturbations
Lead Partner	University Of Leeds, United Kingdom
Partners involved	
Duration	1 April 2021 – 31 March 2023
Results	https://cordis.europa.eu/project/id/101018395/results
Funding	EU-funded
www	https://cordis.europa.eu/project/id/101018395

Nr 330/2022

Co-funded by the Erasmus+ Programme of the European Union