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deep reinforcement learning drl holds considerable promise for motion control of robots with complex dynamics reinforcement learning methods require large amounts of training data this repository provides the full code of sigmarl a sample efficiency and generalization multi agent reinforcement learning marl for motion planning of connected and automated vehicles cavs sigmarl is a decentralized marl framework designed for motion planning of cavs abstract in this paper we address a method that integrates reinforcement learning into the monte carlo tree search to boost online path planning under fully observable environments for automated parking tasks sampling based planning methods under high dimensional space can be computationally expensive and time consuming this paper presents a method for planning motion across a wide range of robotic structures using deep reinforcement learning drl algorithms to solve the problem of reaching a static or random target within a pre defined configuration space however many existing methods struggle to account for the intricate dependencies between joints we introduce coordigraph a novel architecture that leverages subequivariant principles from physics to enhance coordination of motion control with reinforcement learning autonomous navigation for mobile robots has found a promising solution with deep reinforcement learning drl this method stands out for its efficiency particularly because it can operate without requiring extensive labeled datasets during the training process current drl based motion planning approaches can be categorized into two groups drl with discrete action spaces and drl with deep reinforcement learning drl holds considerable promise for motion control of robots with complex dynamics reinforcement learning methods require large amounts of training data exploring a large subset of the relevant state space which can be expensive time consuming or unsafe to obtain we propose relmogen a framework that combines a learned policy to predict subgoals and a motion generator to plan and execute the motion needed to reach these subgoals a wide range of techniques in machine learning itself have been developed and this article describes one of these fields deep reinforcement learning drl the paper provides insight into the hierarchical motion planning problem and describes the basics of drl radosavovic et al developed a reinforcement learning approach for controlling locomotion of a humanoid robot digit they trained their model in simulation and subsequently deployed it into the real world zero shot and showed the potential for robust locomotion on various indoor and outdoor environments in this paper we introduce a curiosity driven reinforcement learner for the icub humanoid robot metta et al 2008 which autonomously learns a powerful reusable solver of motion planning problems from experience controlling the actual physical robot in this work we consider the learning setting where a set of solved motion planning problems is used to improve the efficiency of motion planning on different

yet similar problems this setting is important in applications with rapidly changing environments such as in e commerce among others deep reinforcement learning for motion planning of mobile robots this paper presents a novel motion and trajectory planning algorithm for nonholonomic mobile robots that uses recent advances in deep reinforcement learning we propose a motion planning method for dual arm free floating space robots based on reinforcement learning the problem of slow and unstable convergence of reinforcement learning in high dimensional planning problems is solved by introducing the prior policy of the manipulator inverse kinematics and the infinite norm of the orientation error in this paper an optimized adaptive human machine collaborative torque control methodology is developed for a class of autonomous vehicle systems with unknown disturbances by employing a reinforcement learning technology with identifier critic actor architecture the advantages of reactive motion planning are combined with a policy iteration reinforcement learning scheme to yield a novel solution for unknown workspaces that inherits provable safety convergence and optimality this paper introduces an open source decentralized framework named sigmarl designed to enhance both sample efficiency and generalization of multi agent reinforcement learning rl for motion planning of connected and automated vehicles this article presented a generic reinforcement learning with predictive target information control rlpc method for ehvs to improve the control accuracy in which a distributional soft actor critic dsac iteration frame was established the relative motion between the moving fiber and stationary ink generates a shear force essential for aligning the mesogens in the resin impregnated on the fiber bundle fig 1b in this paper we consider the problem of integrating both path and velocity preferences into trajectory planning for robotic manipulators we first learn reward functions that represent the user path and velocity preferences from kinesthetic demonstration

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subequivariant reinforcement learning framework for

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relmogen integrating motion generation in reinforcement

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a wide range of techniques in machine learning itself have been developed and this article describes one of these fields deep reinforcement learning drl the paper provides insight into the hierarchical motion planning problem and describes the basics of drl

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curiosity driven reinforcement learning for motion planning

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1912 09260 deep reinforcement learning for motion planning

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reinforcement learning based adaptive motion control for

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a tube based reinforcement learning approach for optimal

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4d printing of liquid crystal elastomer composites with

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an incremental inverse reinforcement learning approach for

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