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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 deep reinforcement learning drl holds considerable promise for motion control of robots with complex dynamics reinforcement learning methods require large amounts of training data 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 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 to address this issue we present commonroad rl an open source toolbox to train and evaluate rl based motion planners for autonomous vehicles configurability modularity and stability of commonroad rl simplify comparing different mdps 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 subequivariant reinforcement learning framework for coordinated

motion control haoyu wang xiaoyu tan xihe qiu chao qu effective coordination is crucial for motion control with reinforcement learning especially as the complexity of agents and their motions increases the partially observable markov decision process pomdp 1 provides a mathematical framework to model decision making problems including motion planning of autonomous agents e g unmanned aerial vehicles uavs a reinforcement learning based motion planner for quadrotor autonomous flight in dense environment zhaohong liu1 wenxuan gao2 yinshuai sun3 peng dong abstract quadrotor motion planning is critical for au tonomous flight in complex environments such as rescue oper ations traditional methods often employ trajectory generation constrained reinforcement learning for vehicle motion planning with topological reachability analysis by shangding gu 1 guang chen 1 2 lijun zhang 2 jing hou 2 yingbai hu 1 and alois knoll 1 department of informatics technical university of munich 80333 munich germany 2 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 deep reinforcement learning drl approaches have been applied to the cases of motion planning with continuous state representations however current drl approaches suffer from reward sparsity and overestimation issues it is also challenging to train the agents to deal with complex task specifications under deep neural network approximations 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 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 this paper presents a framework designed to tackle the problem of sample inefficiency and generalization of reinforcement learning rl for motion planning of connected and automated vehicles deep reinforcement learning drl holds considerable promise for motion control of robots with complex dynamics reinforcement learning methods require large amounts of training data 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 this repo contains the code used in the paper monte carlo tree search with reinforcement learning for motion planning ieee itsc 2020 the following algorithms are implemented and benchmarked rules based reflex method a simple emergency braking method in this paper we propose a reinforcement learning rl based cognition enhanced six axis industrial robot for complex motion planning along continuous trajectories as e g needed for welding gluing or cutting processes in production 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

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