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successfully applied to a range of challenging environments, but the proliferation of algorithms makes it difficult to discern which particular approach would be best suited for a rich, diverse task like grasping.

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propose a novel learning architecture capable of navigating an agent, e.g. a mobile robot, to a target given by an image.

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algorithm ...

Deep reinforcement learning (RL) algorithms can learn complex robotic skills from raw sensory inputs, but have yet to achieve the kind of broad generalization and applicability demonstrated by deep learning methods in supervised domains. We present a deep RL method that is practical for real-world robotics tasks, such as robotic manipulation, and generalizes effectively to never-before-seen ...

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Vision-Based Deep Reinforcement Learning for Robot Navigation
Background The goal of this project is to apply reinforcement

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learning (RL) to control a robot in the task of autonomous navigation. As a first step, experiments would be conducted in the virtual world where the task and environment can be configured on demand.

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25/5/2018 · Abstract: In this paper, we explore deep reinforcement learning algorithms for vision-based robotic grasping. Model-free deep reinforcement learning (RL) has been successfully applied to a range of challenging environments, but the proliferation of algorithms makes it difficult to discern which particular approach would be best suited for a rich, diverse task like grasping.

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deep RL agent's tasks such as in this paper [11]. In [12] propose new memory based deep reinforcement learning architectures for Minecraft and discuss how it can tackle the problems of current RL systems like partial observability, delayed rewards, high dimensional visual observation, etc better. They are show that their model generalizes ...

process for mapping. [30] propose a kernel-based reinforcement learning algorithm for large-scale settings. [31] use RL for making

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decisions in ATARI games. In contrast to these approaches, our models use deep reinforcement learning to handle high-dimensional sensory inputs. Recently, methods that integrate deep learning methods

based deep reinforcement learning in real-world roboticmanipulation. 2 RelatedWork 2.1 Vision-based Robotic Manipulation Vision-based robotic manipulation is the process by which robots use their manipulators (such as robotic arms) to

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rearrange environments [Mason, 2001], based on camera images.

B.1. Training ADNet with Reinforcement Learning (Section 4.2)

The detailed algorithm to train ADNet with reinforcement learning is described in Algorithm 1. The initial network parameter W^{SL} is the same as W^{SL} (line 1). In the training iteration, we randomly select a piece of training sequences f^l $l=1$ and the ground truth f^l

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Reinforcement Learning (RL) has been applied to a variety of problems, such as robotic obstacle avoidance [2], and visual navigation [1]. Deep Reinforcement Learning (DRL), a combination of reinforcement learning with deep learning has shown unprecedented capabilities at solving tasks such as playing Atari games or the game of

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value-based method which combines deep learning with Q-learning, with the learning objective to optimize the estimates of action-value function [6]. 2.3 Reinforcement learning in financial market Reinforcement learning has been an area of interest for both

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IMAGE-BASED PATH PLANNING IMAGE-BASED VISUAL SERVOING DEEP REINFORCEMENT LEARNING Allowing the robot to reach a final configuration by following the strategy learned during a training phase No 3D pose estimation, once training phase has ended [Xie, 2017] [Zhao, 2020] Impracticability of applying Reinforcement Learning directly on real world robots

Evolving Deep Unsupervised Convolutional Networks for Vision-Based Reinforcement Learning By J. Koutník, J. Schmidhuber,

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Online Evolution of Deep Convolutional Network for Vision-Based Reinforcement Learning Jan Koutník, Jürgen Schmidhuber, and Faustino Gomez IDSIA, USI-SUPSI Galleria 2 Manno-Lugano, CH 6928 {hkou,juergen,tino}@idsia.ch Abstract. Dealing with high-dimensional input spaces, like visual input, is a challenging task for reinforcement learning (RL).

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Reinforcement learning explores policies through trials, and has been applied to vision based obstacle avoidance in [13]. However,

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the raw image is encoded as several levels of depth to predict a suitable control strategy. Deep reinforcement learning (DRL) has recently been shown to achieve superhuman

Action-Decision Networks for Visual Tracking with Deep Reinforcement Learning Sangdoon Yun¹ Jongwon Choi¹ Youngjoon Yoo² Kimin Yun³ and Jin Young Choi¹ ¹ASRI, Dept. of Electrical and Computer Eng., Seoul National University, South Korea ²Graduate School of Convergence Science and Technology,

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Seoul National University, South Korea 3Electronics and Telecommunications Research ...

Keywords: Visual-Inertial, Calibration, Model-based Deep Reinforcement Learning, Markov Decision Process, Particle Swarm Optimization 1 Introduction In recent years visual-inertial (VI) sensors, which consist of one or more cameras and an inertial measurement unit (IMU), have become increasingly popular for robust high frequency motion

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30/11/2018 · This work in this post is based on the following paper: **Visual Foresight: Model-Based Deep Reinforcement Learning for Vision-Based Robotic Control** Frederik Ebert*, Chelsea Finn*, Sudeep Dasari, Annie Xie, Alex Lee, Sergey Levine Project webpage; The above paper is an extended version of the following four papers, and builds upon the fifth paper:

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