

CS234 Winter 2019

MuJoCo License and Installation Guide

February 16, 2019

[MuJoCo](#) stands for Multi-Joint dynamics with Contact that will be used in assignment 3 and also many RL papers use it as a benchmark.

We have provided MuJoCo license for enrolled students in CS234. You can also use the license for your projects. Please **Do not share this license with anyone outside the class**. This is part of our user agreement, that only **enrolled** students, CAs and the instructor can use the license.

MuJoCo Installation Guide

Prerequisites: Python3.6 and Tensorflow 1.7.1

Windows users: We recommend you do this assignment on a Linux VM. You can use your Azure instance from assignment 2. If you need more Azure credit for this, email wuy@stanford.edu to request more.

1. Download **mujoco131** for your OS [here](#). Be sure to download version 131

VM users can scp this to their machine, or download directly using:

```
wget https://www.roboti.us/download/mjpro131_linux.zip
```

2. Extract the downloaded package to `~/.mujoco/mjpro131`

```
unzip mjpro131_*.zip -d ~/.mujoco
```

3. Download the license file and place it in `~/.mujoco/mjkey.txt` from [here](#) (Only enrolled students and CAs have access to this).
4. Install the following dependencies:

```
pip3 install gym==0.9.1
pip3 install mujoco-py==0.5.7
pip3 install scipy
pip3 install matplotlib
```

5. VM users: Edit `config.py` to set `self.record = False` in the three environment config objects.
6. Verify that the following command doesn't throw a fatal exception (`PkgResourcesDeprecationWarning` is fine)

```
python3 -c 'import gym; gym.make("InvertedPendulum-v1")'
```