Deep Reinforcement Learning for Robotic Grasping from Octrees

Learning Manipulation from Compact 3D Observations

Andrej Orsula

Robotics

Master's Thesis

BREAKING NEW GROUND

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Resumé

TODO: Resumé in Danish

Preface

This Master's Thesis is written by Andrej Orsula as the final work of M.Sc. programme in Robotics at Aalborg University during the academic year 2020/21.

Acknowledgements

Special thanks goes to Simon Bøgh for his supervision, guidance and numerous discussions throughout the whole process that helped to shape this project. Moreover, I must express a very profound gratitude to my mum, dad, sister and brother for their love and everlasting support.

Additional Resources

The primary source code developed during this project is available on the following *GitHub* repository.

- https://github.com/andrejorsula/drl_grasping

All readers interested in reproducing the results from this work are welcome to use pre-built *Docker* images that can be found inside the *Docker Hub* repository below.

- https://hub.docker.com/r/andrejorsula/drl_grasping

This manuscript and additional resources such as raw data acquired during the testing can be accessed using the following *GitHub* repository.

- https://github.com/andrejorsula/master_thesis

Glossary

2D	Two-dimensional
3D	Three-dimensional
MDP	Markov Decision Process
RL	Reinforcement Learning
DRL	Deep Reinforcement Learning
DDPG	Deep Deterministic Policy Gradient
TD3	Twin Delayed Deep Deterministic
SAC	Soft Actor Critic
TQC	Truncated Quantile Critics
CNN	Convolutional Neural Network

1 Introduction

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Bibliography

Name, R. (2000). Fascinating title. *Journal of Testing 420*(69), 69–420.

Appendices

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Test citation (TODO: remove test citation): (Name, 2000)