

LunarLander with erratic gravity

Train network on predicting next state

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- ▶ $g_{current} = \arg \min_g \text{dist}(\text{state}_{actual}, \text{state}_{g;predicted})$

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- expensive
 - ▶ new head for state prediction, keep backbone same
 - ▶ new head/input/network per environmental state (here just flip lander)