A Graph-Based Search Approach to Planning and Learning

G.S. Groote

Supervisors: C. Pezzato
M. Wisse
C. Smith

Delft University of Technology, The Netherlands

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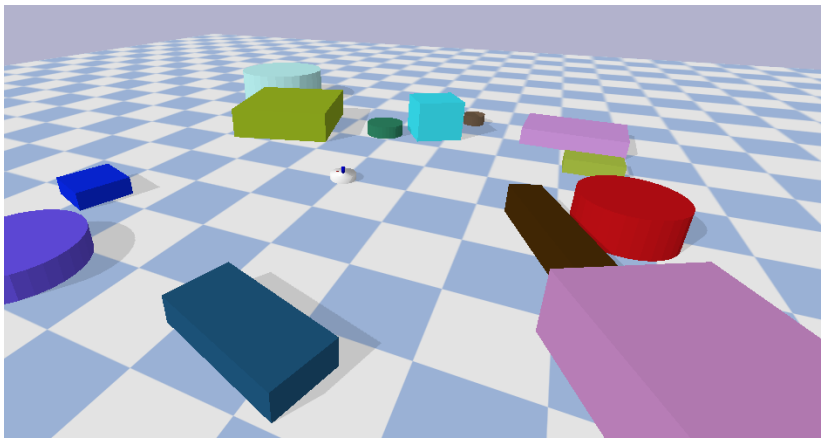
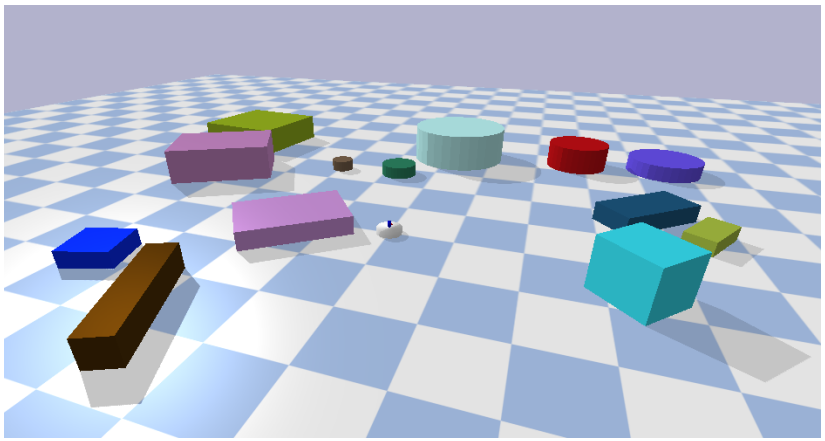
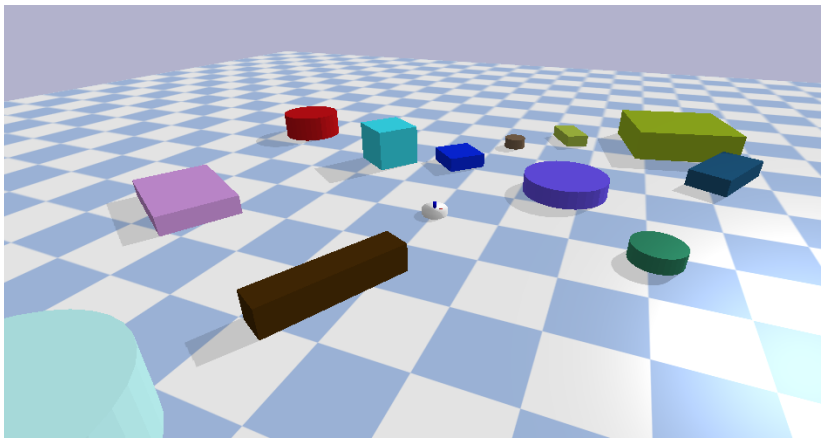
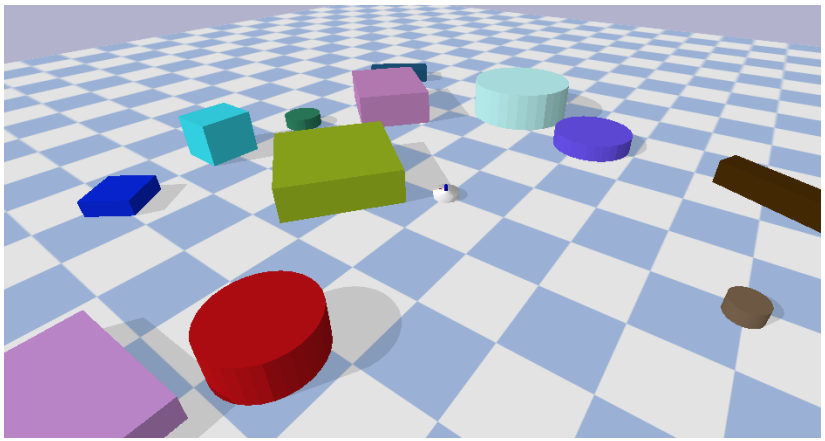
Results: Randomisation Drive Task

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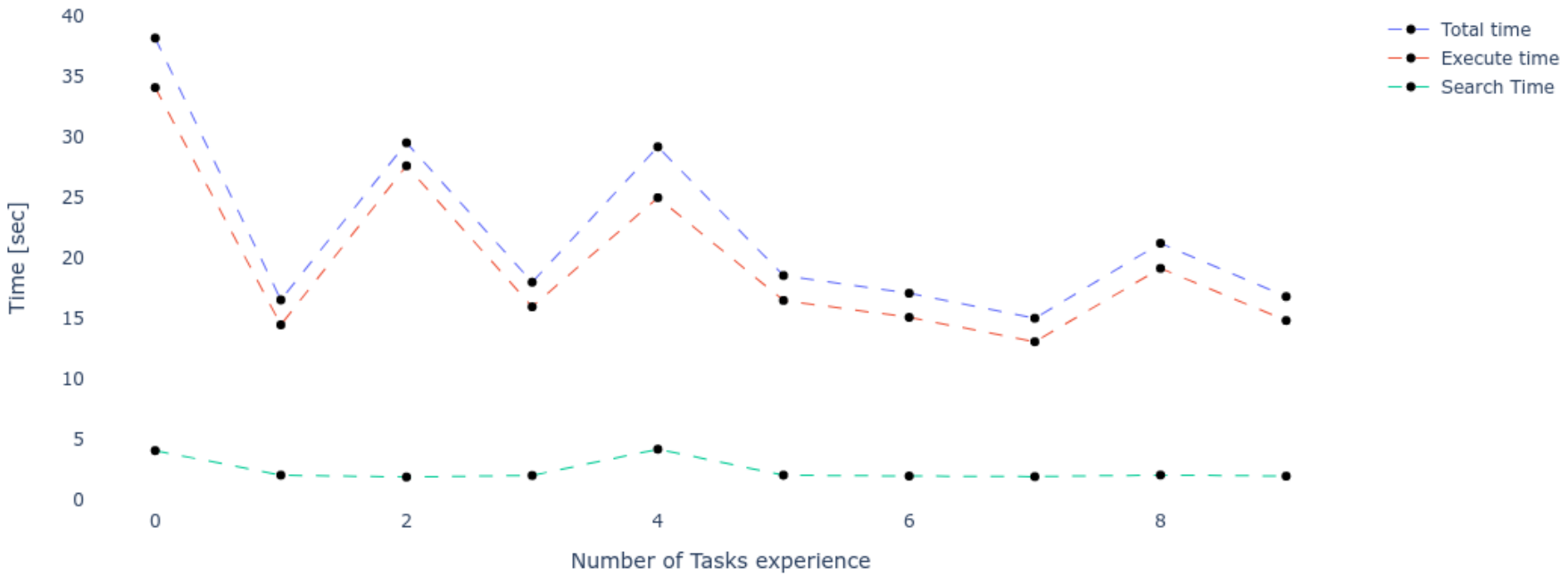

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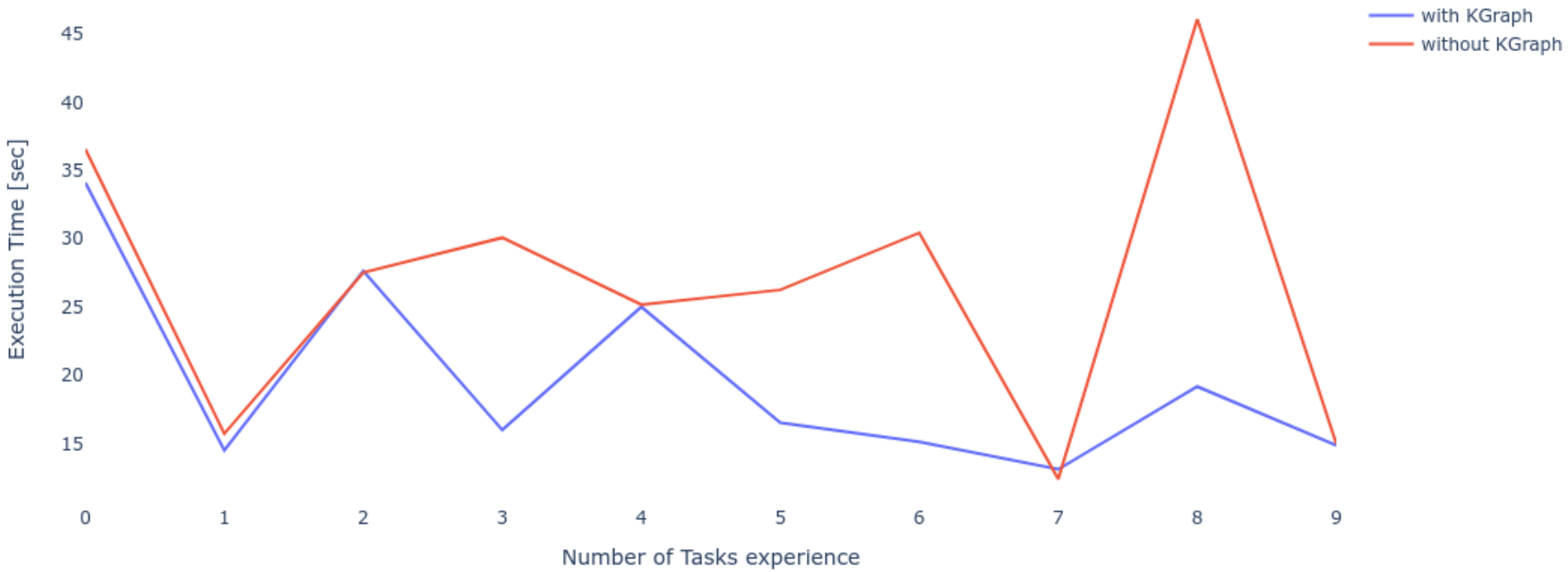
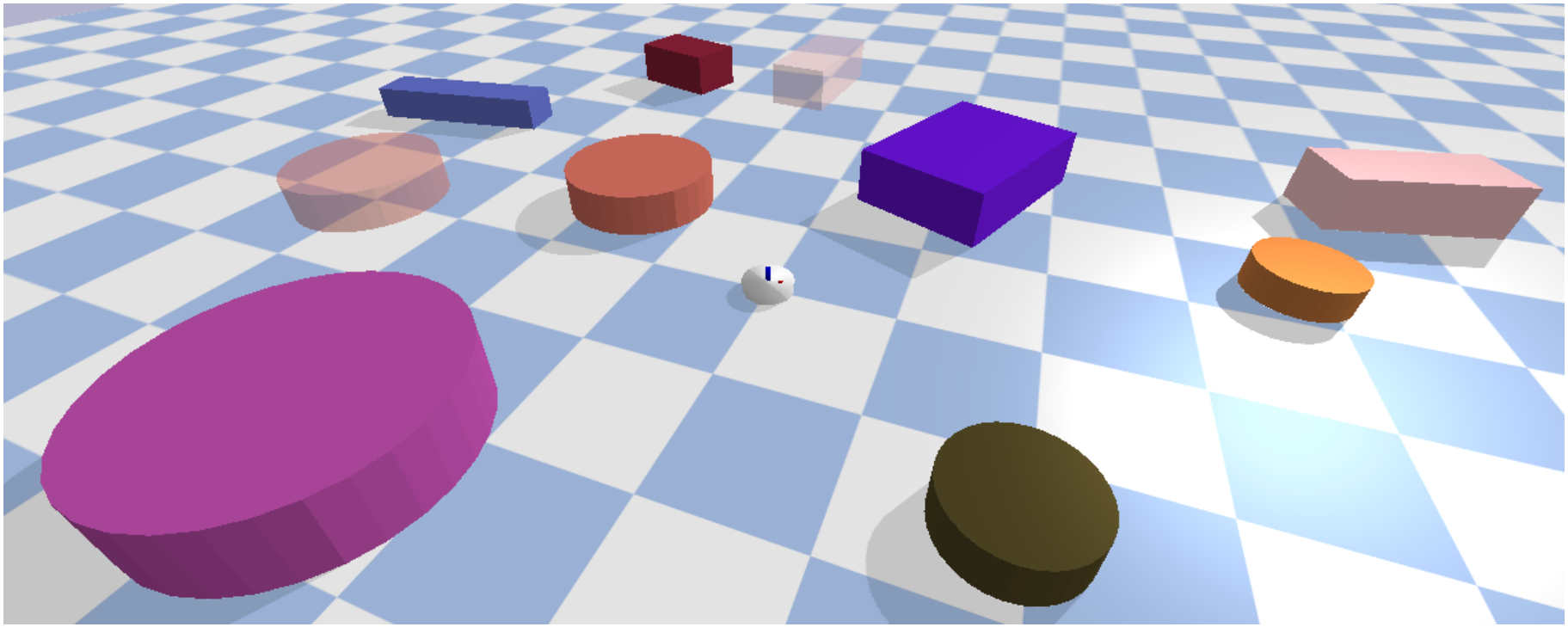
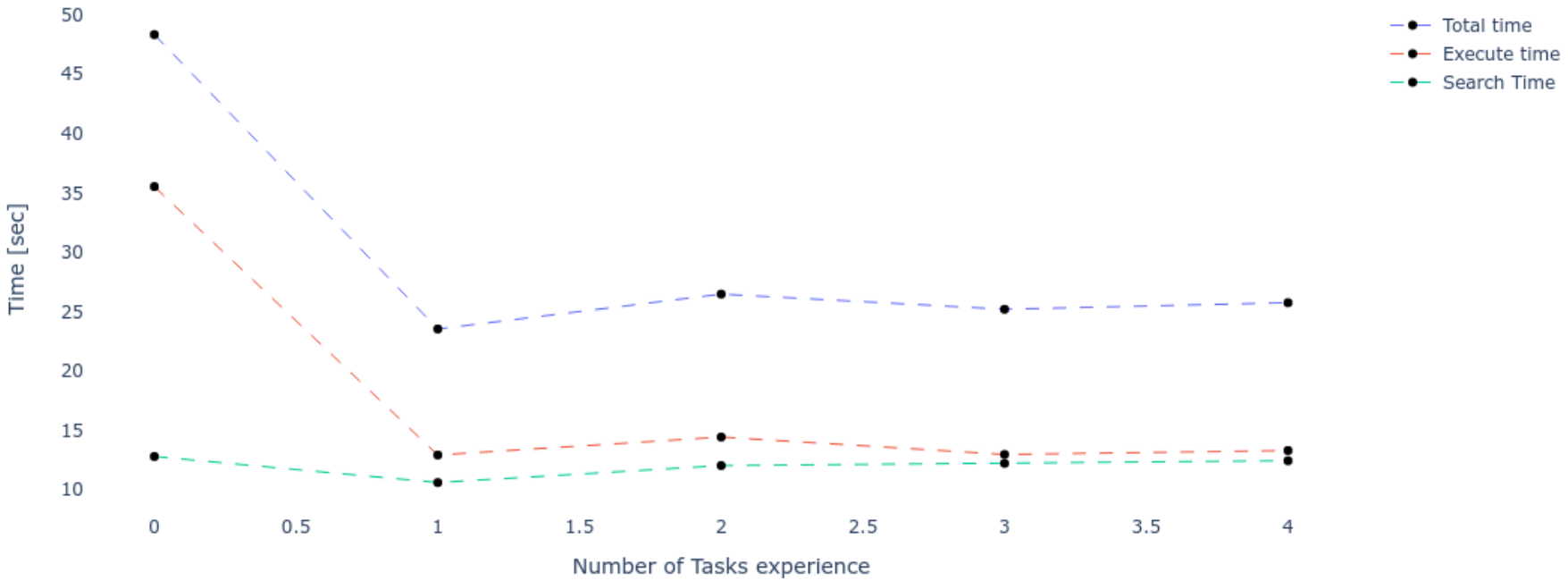


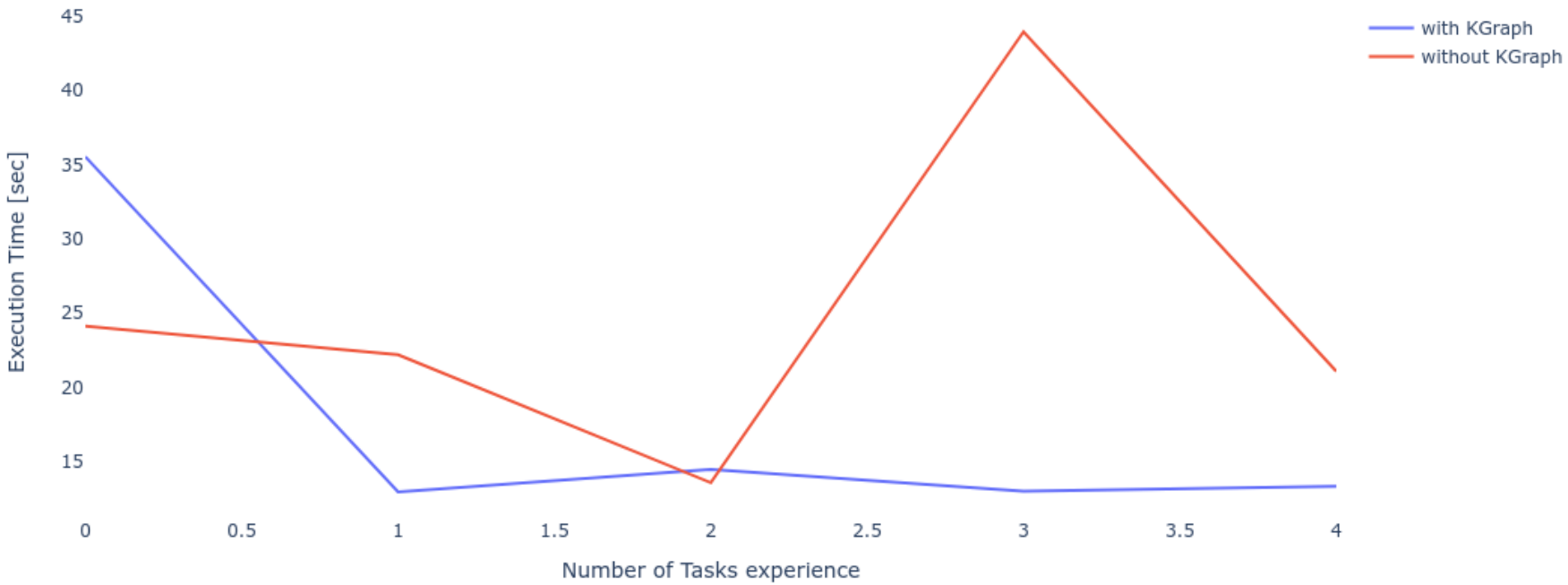
Results: Randomisation Push Task



Results: Randomisation Push Task



Results: Randomisation Push Task



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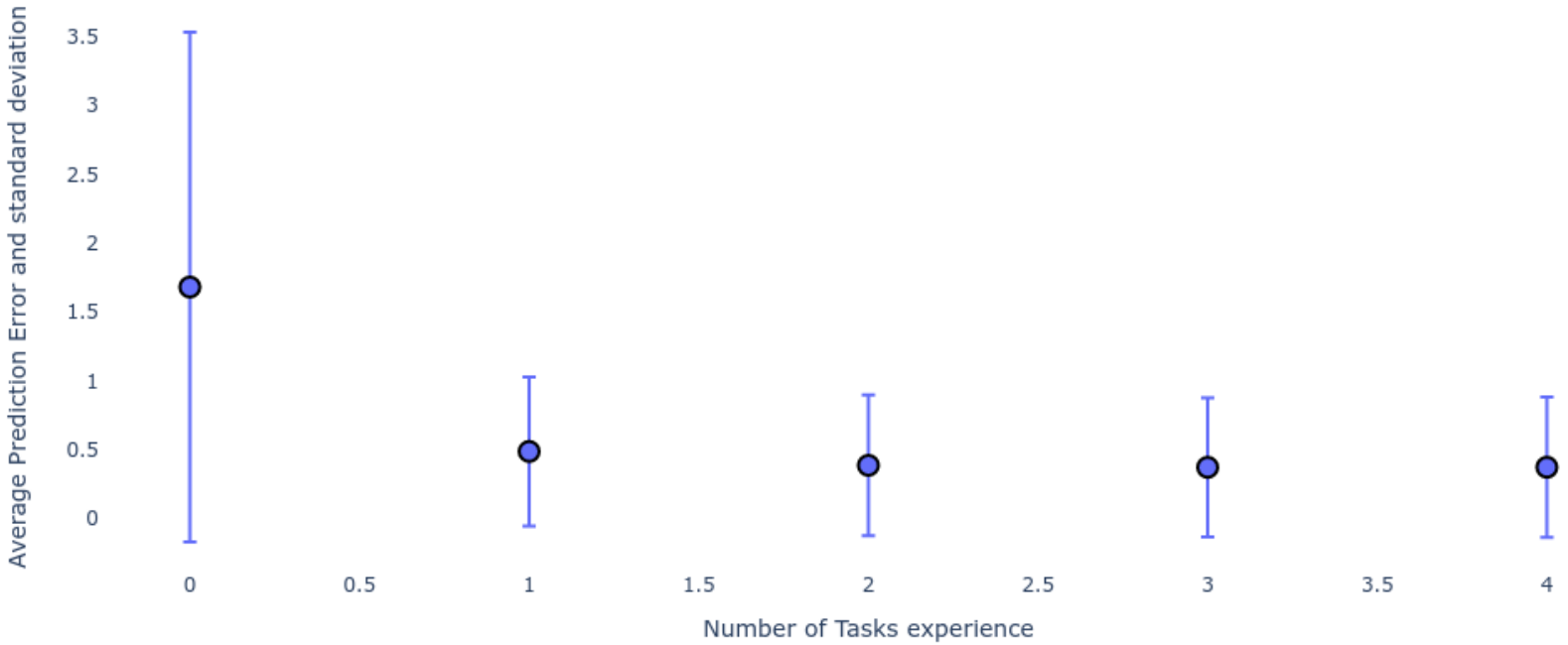
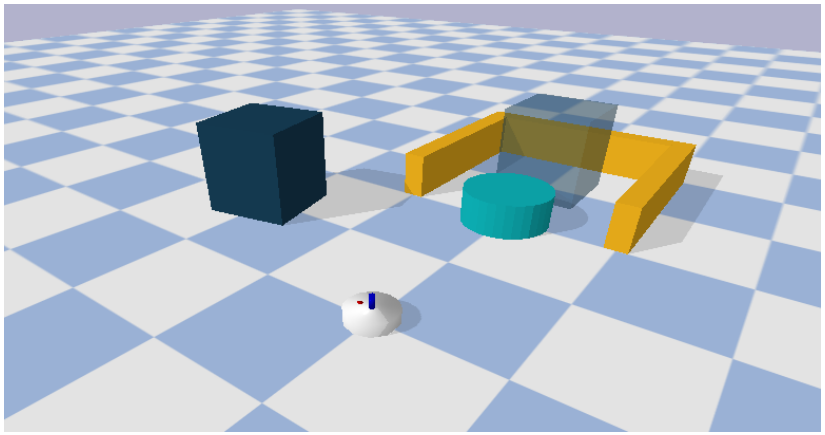
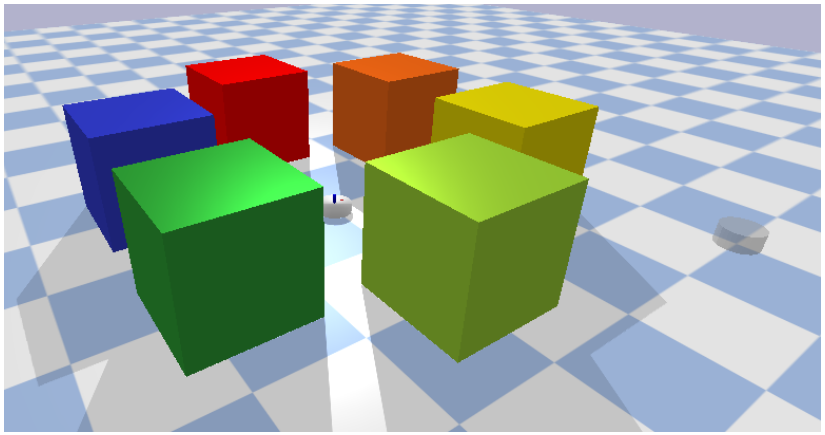


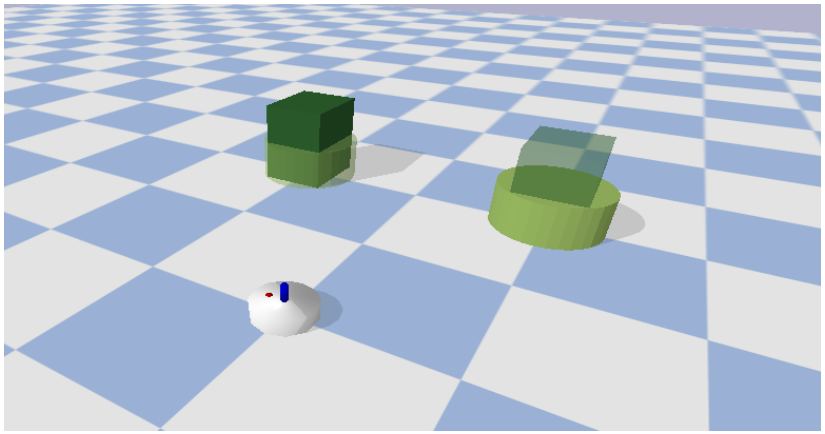
Results

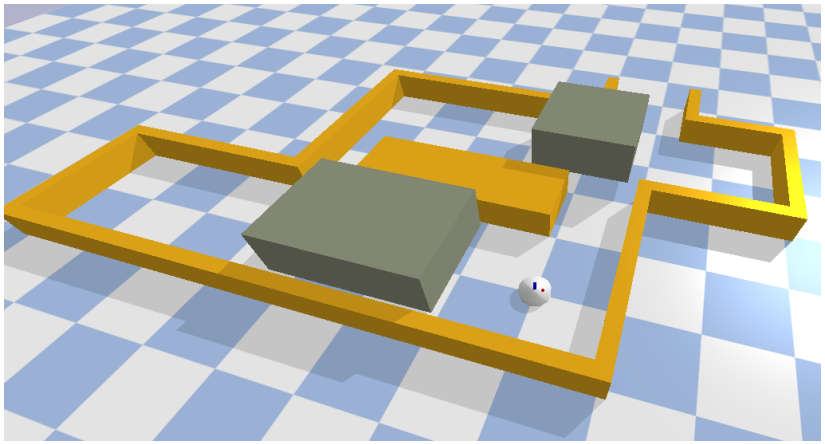
Author	Learning	NAMO	Object to Target	Manipulation
Ellis et al.	✓	✓	✗	pushing
Sabbagh Novin et al.	✓	✗	✓	grasp-push grasp-pull
Scholz et al.	✓	✓	✗	graph-push grasp-pull
Vega-Brown et al.	✗	✓	✓	gripping
Wang et al.	✓	✓	✗	pushing
Groote	✗/✓	✓	✓	pushing

More convincing environments









4 Week Planning

Good Scenario

- 50 % Report
- 50 % Presentation

4 Week Planning

Good Scenario

- 50 % Report
- 50 % Presentation

Better Scenario

- 40 % Report
- 40 % Presentation
- 20 % Benchmark Environments