**README**

**This is a confidential code repository only meant for reviewers, please refrain from sharing this link**

**\*Make sure you are signed in.**

1. Requirements -
   1. Python 3.7+
   2. PyTorch==1.10.0 and cuda11.3
   3. numpy==1.21.4
   4. gym==0.15.7
   5. Hardware : Cuda supported GPU with atleast 4GB memory
2. Install mujoco200 using <https://roboti.us/download/mujoco200_linux.zip>
3. Install Safety Gym using <https://github.com/openai/safety-gym>
4. For reproducing results (upto same extent because of seed randomness) -
   1. Take backup of **/…/safety-gym/safety\_gym/envs/suite.py**
   2. Copy ./src/env\_suite\_file/suite.py to above path.
   3. Change ‘num\_steps’ = 750’ in ‘DEFAULT’ dict of class Engine in **/…/safety-gym/safety\_gym/envs/engine.py**
   4. Run for 8 random seeds :
      1. cd src
      2. python3 mbppo\_lagrangian.py –exp\_name=”experiment\_name” –seed=0 –env=”<environment\_name>” –beta=0.02

Where environment names are [Safexp-PointGoal2-v0,Safexp-CarGoal2-v0]

1. Use <https://github.com/openai/safety-starter-agents/blob/master/scripts/plot.py> for plotting -

python plot.py –logdir=’<path to data>’’ --value=<plot\_choice>

Where plot\_choice are ‘AverageEpRet’ for reward performance, ‘AverageEpCost’ for cost performance.