First experiment

LIDAR obstacle detection

Location and distance of obstacle in the front cone
(left and right separately ?)

Too close in the front cone

-100

observation

Wheels and steering controller

+
+
+

reward

action

AGENT

Stop panel depth detection

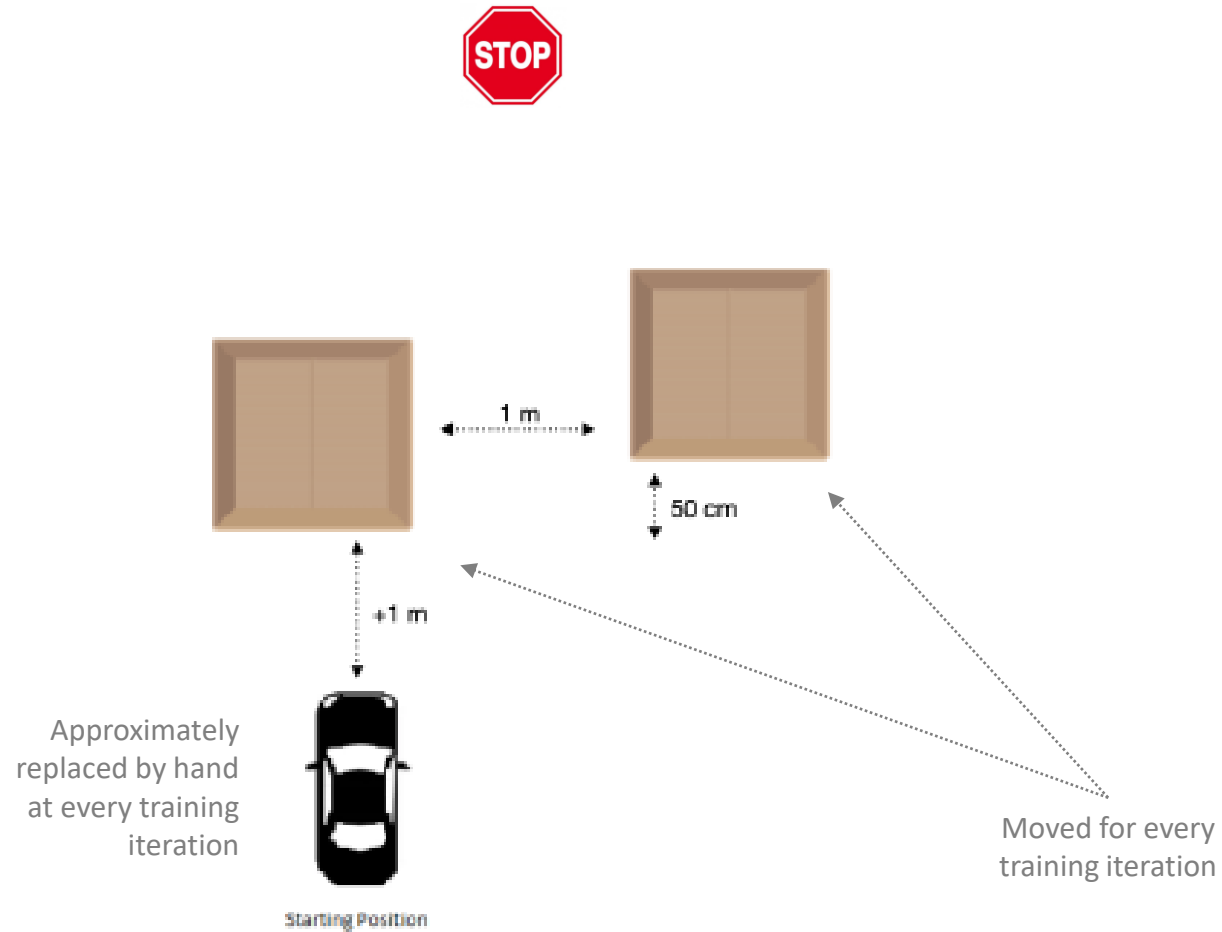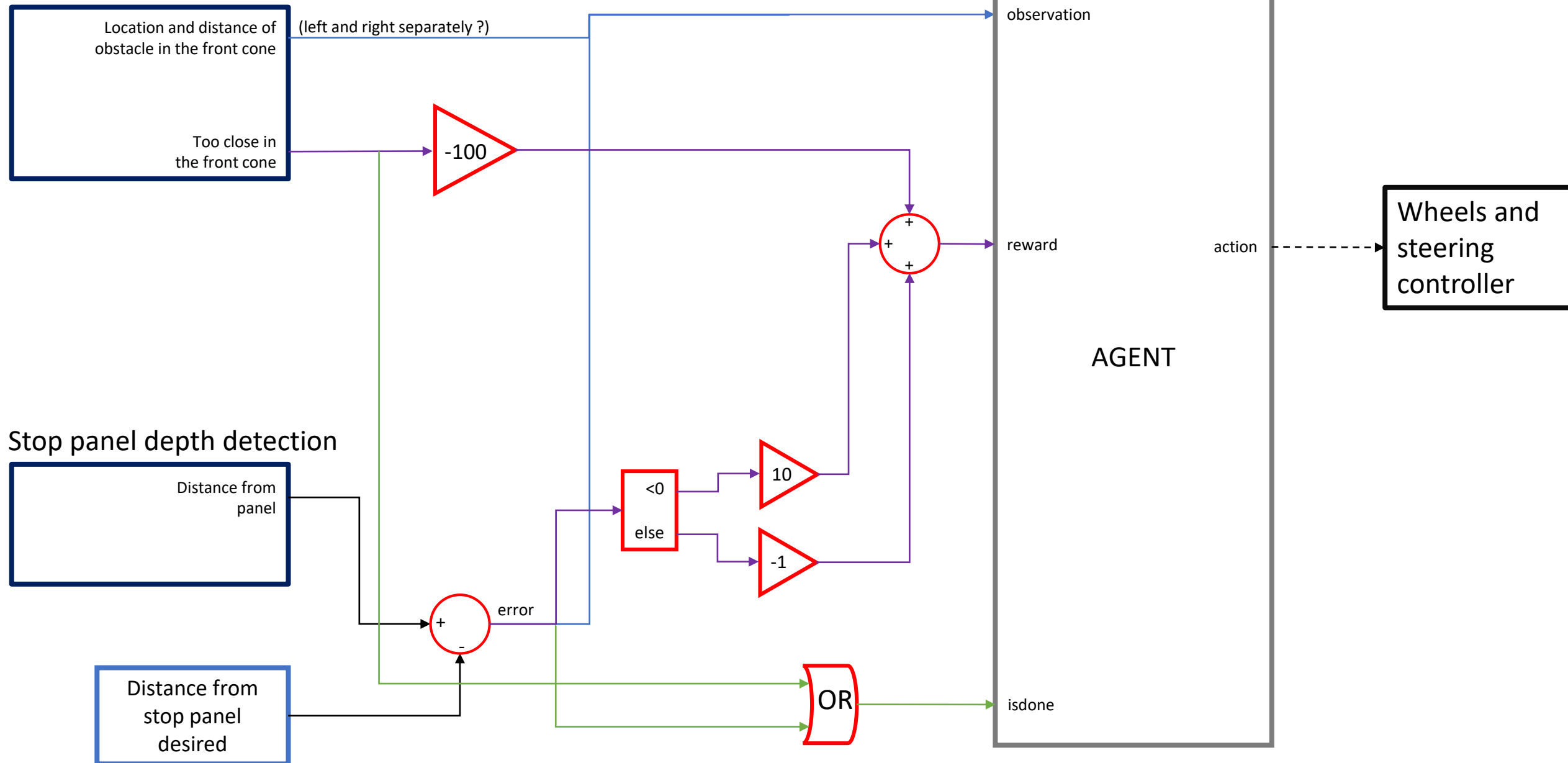Distance from panel

<0

else

10

-1

error

Distance from stop panel desired

+
-

OR

isdone

Agent dimensions

- Actor-critic networks ?
    - Same as MATLAB water tank example ?

- Training specifications ?

- Use of real robot for training ?
    - Long to do, must manipulate the robot and obstacles at every iteration