



```

R_Obstacle_Avoidance.py
...
def __init__(self, args):
    self.resetCollision()
    self.resetCollision()
    self.controller.start()
    self.add_collision_sensor()
    self.add_lidar_sensor()
    self.add_camera()

```

EnhancedPedestrianEvgenyEnd

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CarlaPedestrianR\_Obstacle\_Avoidance

approx_n	0.01/0.0006
clip_fraction	0.29
clip_range	0.2
entropy_loss	-1.97
explained_variance	0.239
learning_rate	0.0002
loss	-0.00297
n_updates	0
policy_gradient_loss	-0.0038
value_loss	0.0008

