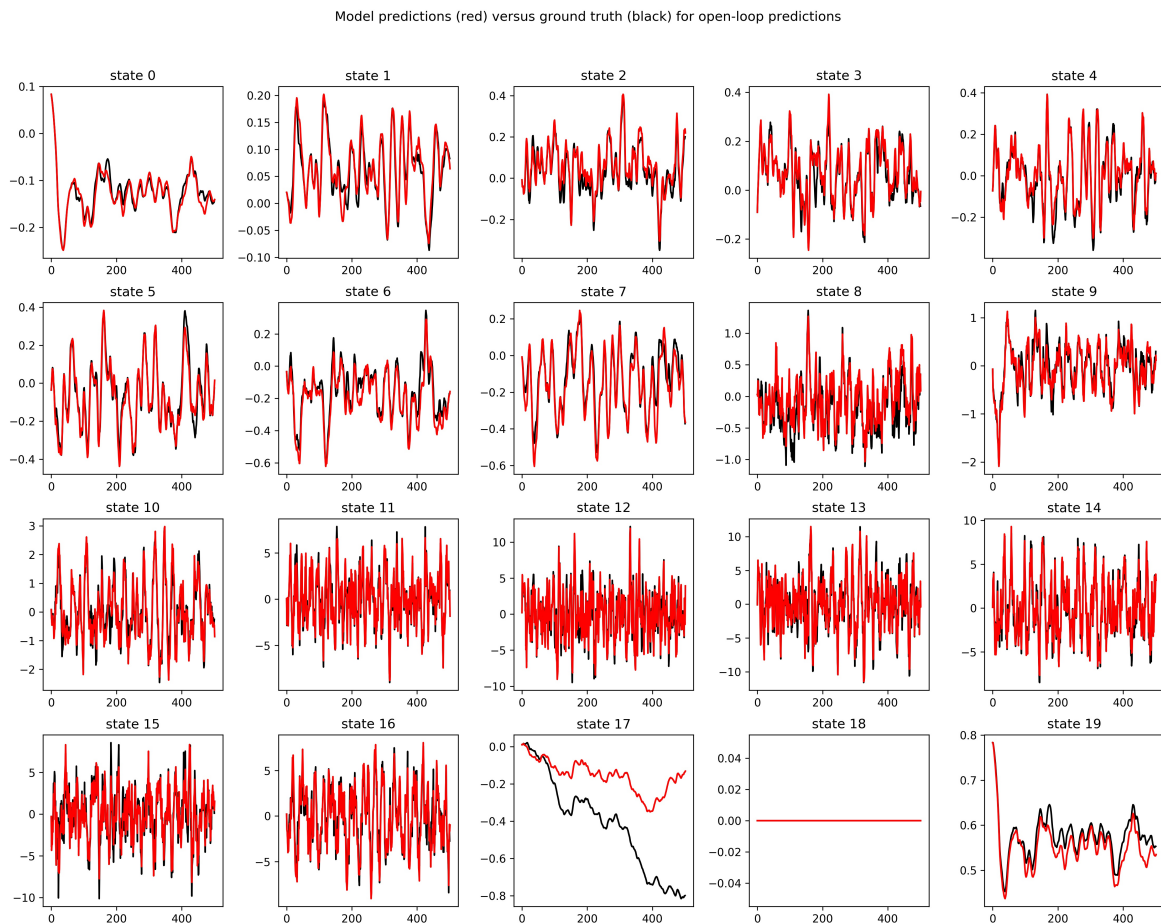


# Berkeley DRL HW4

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## PROBLEM 1



In every dimension except 17<sup>th</sup> the predictions of the model are almost exactly the same as the ground truth. In state dimension #17 predictions are getting much different from the truth : small errors accumulated over time because each successive state was predicted based on erroneous previous state

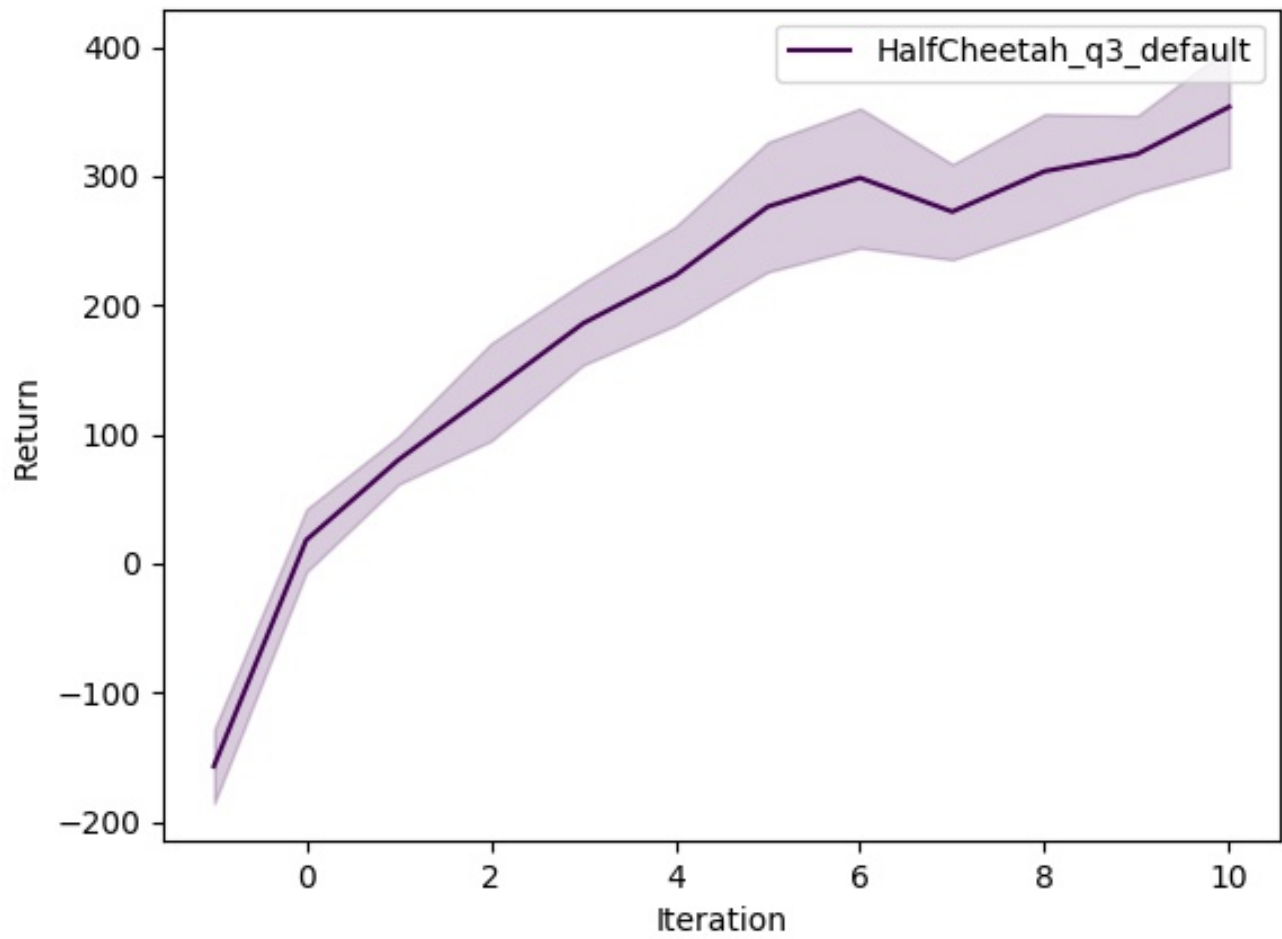
## PROBLEM 2:

Comparison of the performance of the model based controller trained on a random data versus the random policy:

	Model Based Controller	Random Policy
ReturnAvg	-162.79	28.00
ReturnStd	-11.47	19.30

### PROBLEM 3(A)

Model Based RL policy return increases with iterations



### PROBLEM 3(B)

Comparing performance for varying [number of nn layers, length of MPC horizon, number of ranom actions]

