# Reflection report Tinlab Machine Learning

**Thomas Alakopsa**
**0911723**

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# Contents

# 1 Introduction

This is my reflection on my performance on the 5 competents: advise, analyze, manage, design and realize. In the course: tinlab machine learning.

# 2 relfection

## 2.1 advice

The tinlab machine learning does not invlove stakeholders or anything else that requires any advice, hence there is no way to reflect on my advicing skills.

## 2.2 analyse

Analysing was a crusial part of this tinlab. I personaly had no expierence with machine learning before, so i had a lot too learn. There where a lot of opertunities given to learn about machine learning and the important information serounding it by the teachers like: slides, books and articals. A summery of this can be found in my personal report. Sometimes is was quite difficult to understand the informations that the articals tried to covey, because they are writen in a very direct and sientific way that assumes you have a lot of foreknowledge about machine learning, wich frankly i did not have. That made it very hard to read and the teacher did little to none for making it more understandable, but I could have put in even more effort too. In short I put enough effort in the understand everything that I needed too but not everything. This is mainly because the matrials was to hard to understand with my lack of general knowledge and assistance.

## 2.3 design

Designing was not very pressent in this project, but I did designed most of the neural networks in the ways of how many nodes and hidden layers we use and why that number.

## 2.4 manage

Alex and I decided to use Agile project managent with the help of trello for the system to manage the project. Almost every day we had meeting to talk about the progress that was made the day before and too discuss what task we will be worked on that day. For version management we used git for both the reports, code and the neuralnetworks. The git log can be found in the main report. Using git was sometimes a but frustrating but very usefull when we needed to ga back to an olderversion.

### 2.5 realise

We have made a controller that can finish all the road tracks in torcs with -noisy on. This is done with a trained neuralnetwork and a getback on track functions. This functions takes control of the car if it crashes and gets it back on the track before it gives control back too the neural network.

## 3