

Agile Trajectory Generation for Tensile Perching with Aerial Robots

Progress Update

Focussed around the learning from previous demos of the approaching stage.

- Using a Soft Actor Critic from Demonstrations algorithms
 - Training at the moment.
 - Currently in 2d (y coordinate fixed) - planning to extend to 3d
 - Aiming to have more concrete results by friday.

Overall Progress

- Previously been mostly focussed on courseworks deadlines.
- This week I have turned attention back to project.
- Planning to take 13th - 27th (2 weeks) off for exams + a few days of holiday.

Questions

- Demonstrations - Is there anything I can do for this?