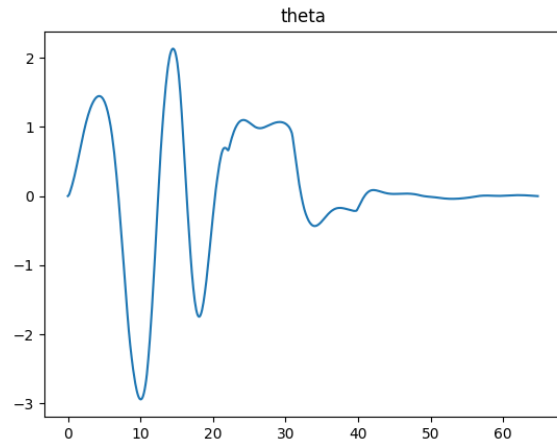
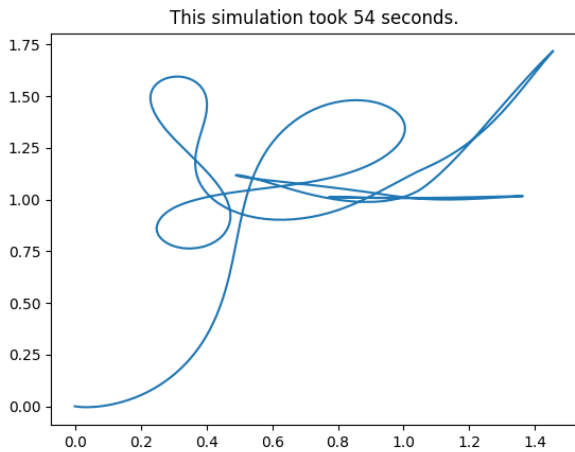
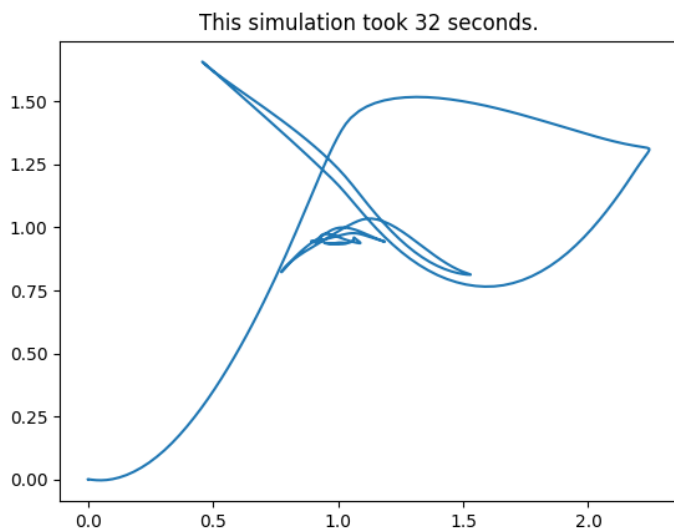
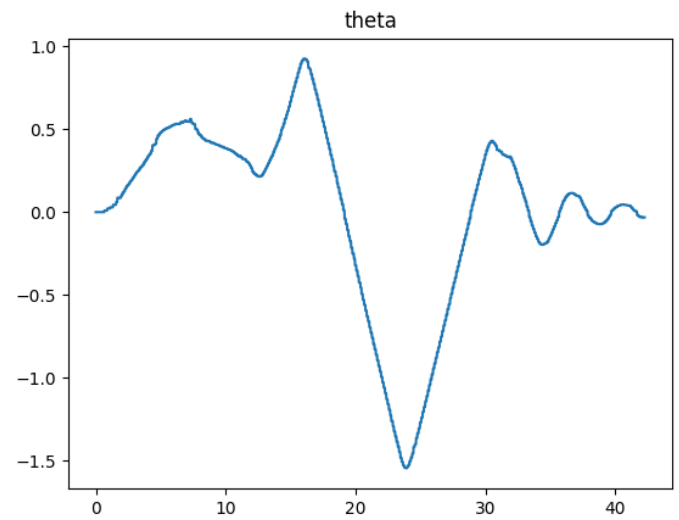
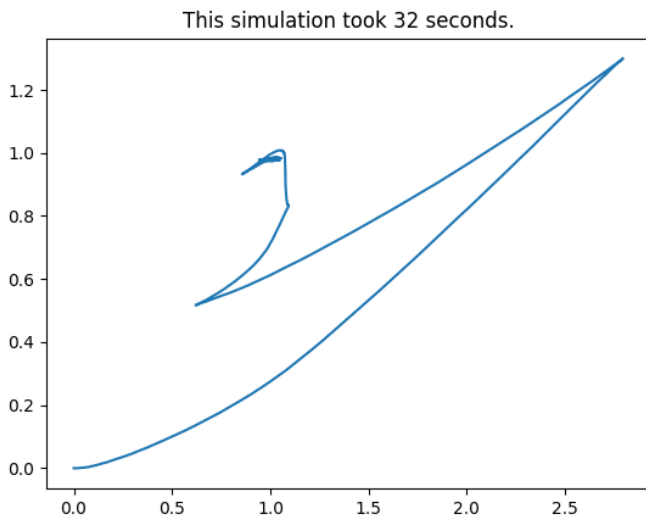


Résultats pour erreur à 5 % durant 10 secondes, thetashifratio=1 size=2

Gain=1, Learning step=0.5, Starting position (0,0,0), Target position (1,1,0)
Simulation :

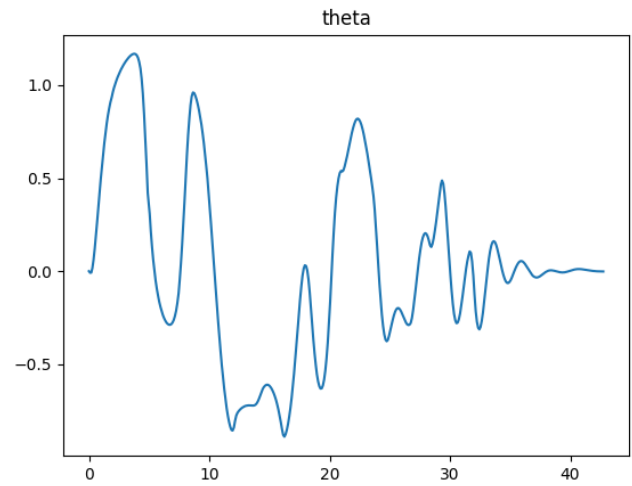


Robot :

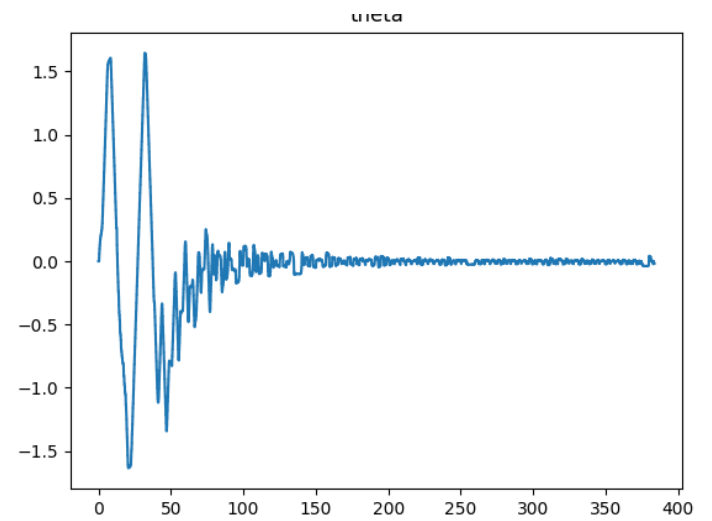
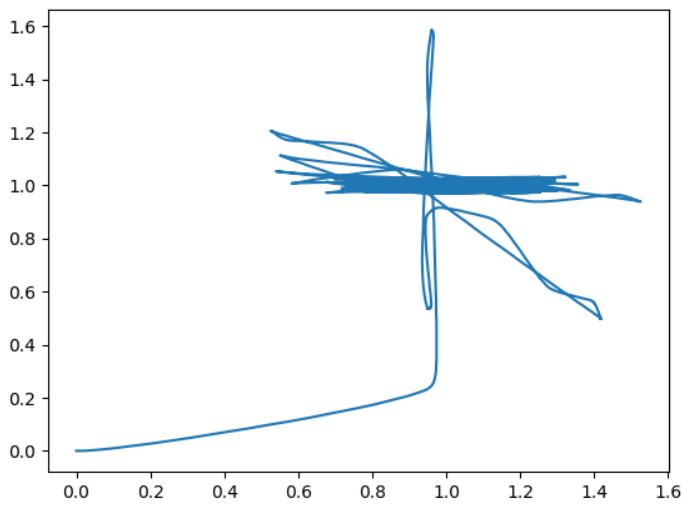


Gain=5, Learning step=0.5, Starting position (0,0,0), Target position (1,1,0)
Simulation

Robot



This simulation took 373 seconds.



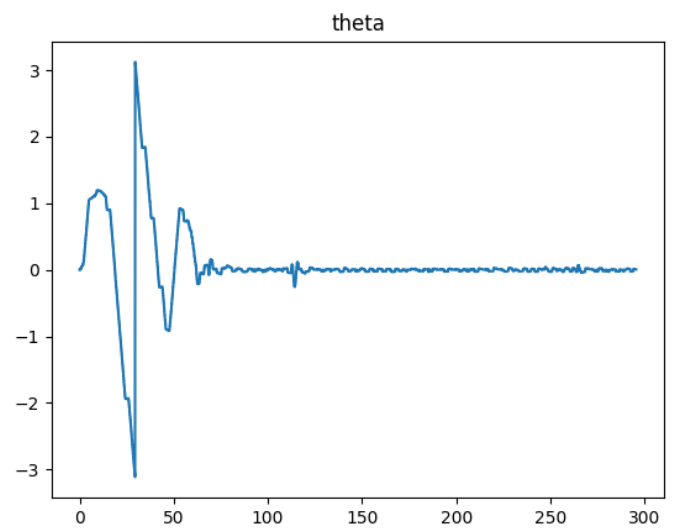
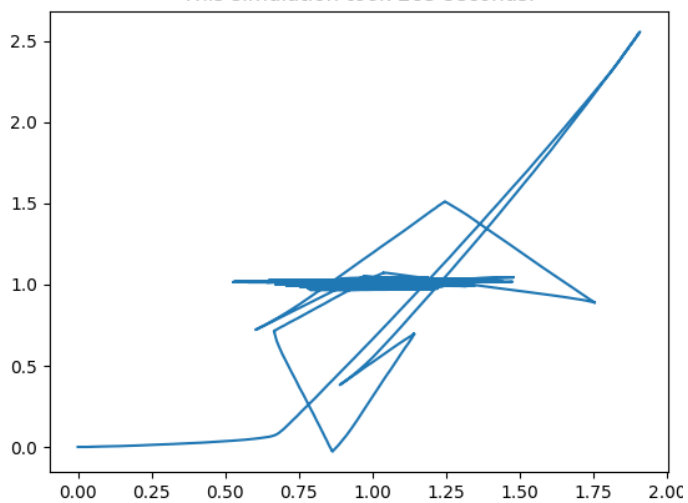
Gain=10, Learning step=0.5, Starting position (0,0,0), Target position (1,1,0)

Simulation

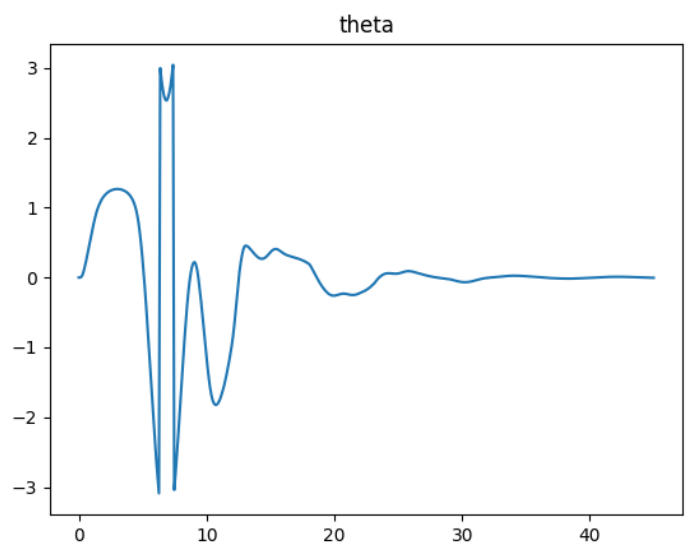
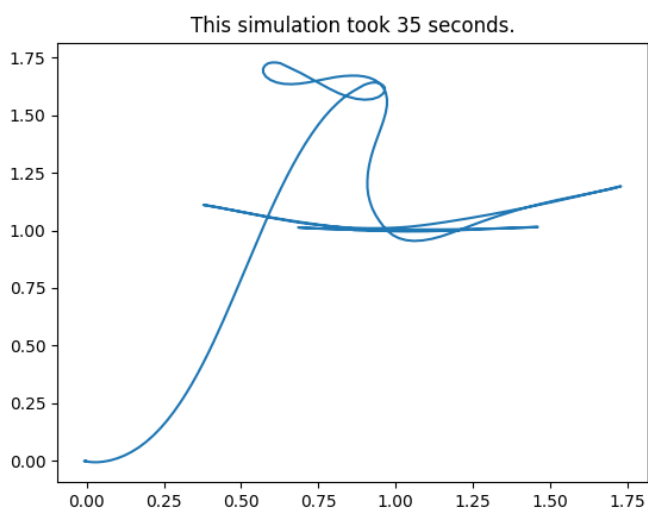
ne converge pas

Robot

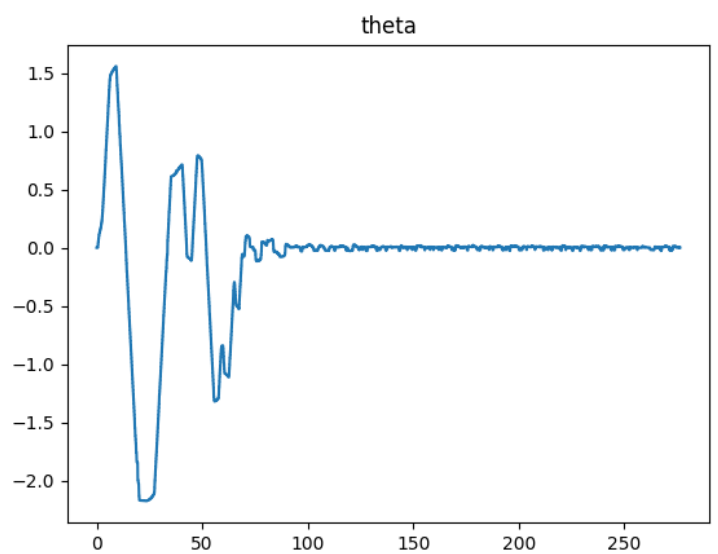
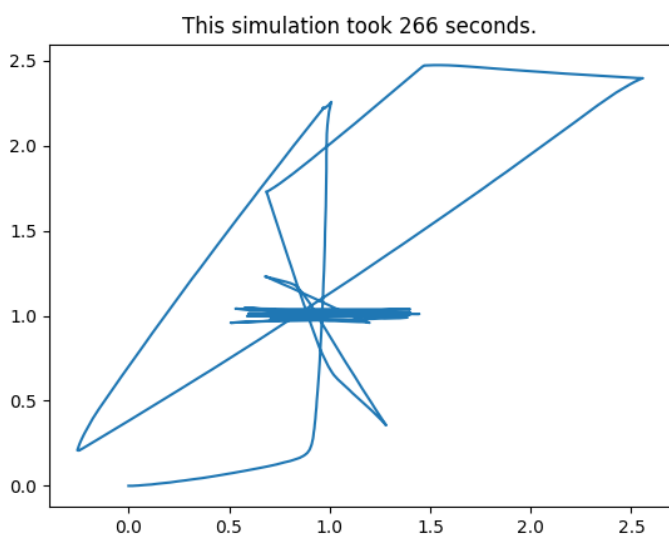
This simulation took 285 seconds.



Gain=10, Learning step=0.2, Starting position (0,0,0), Target position (1,1,0)
Simulation

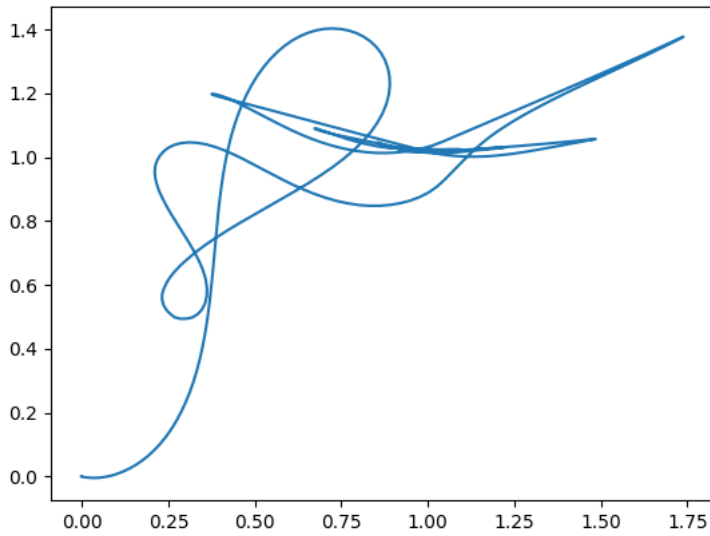


Robot

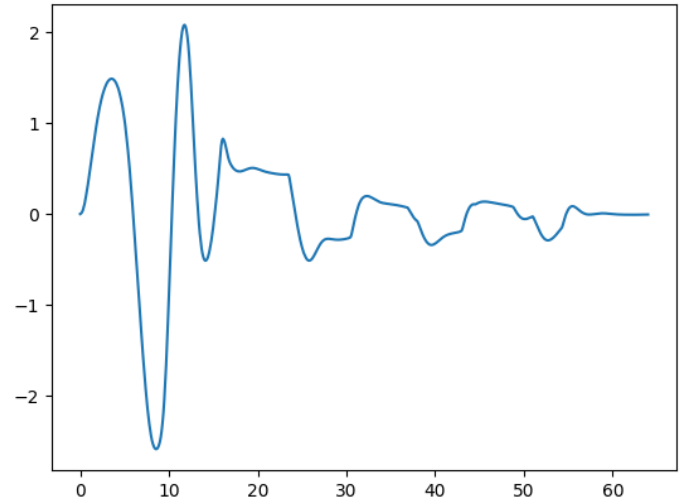


Gain=10, Learning step=0.1, Starting position (0,0,0), Target position (1,1,0)
Simulation

This simulation took 54 seconds.

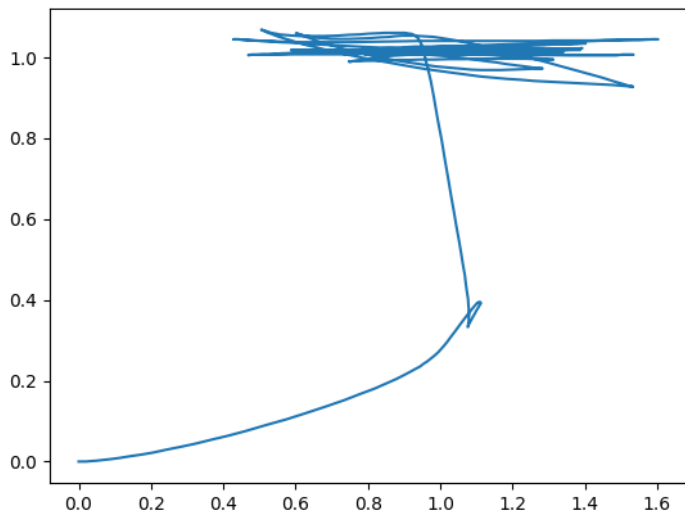


theta

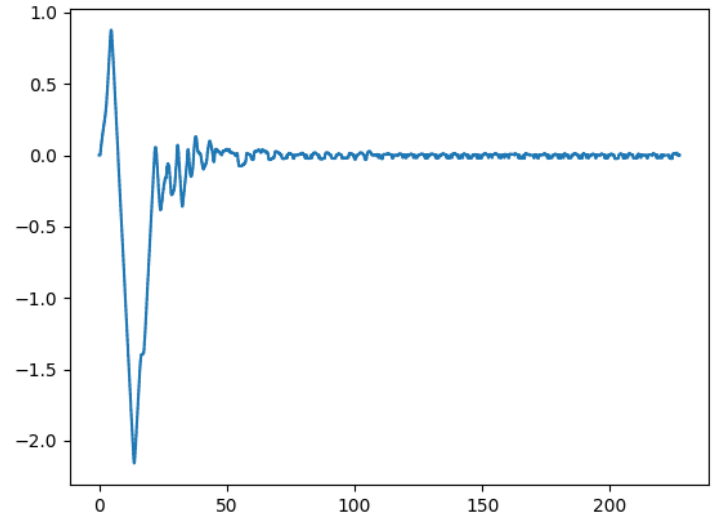


Robot

This simulation took 217 seconds.

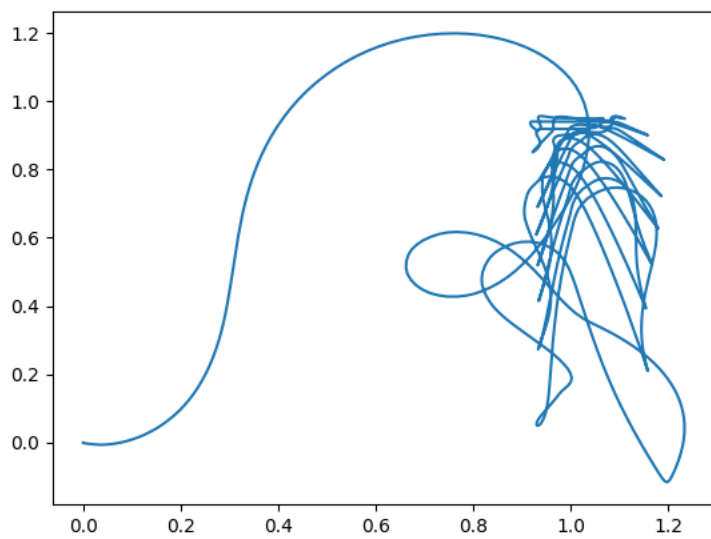


theta

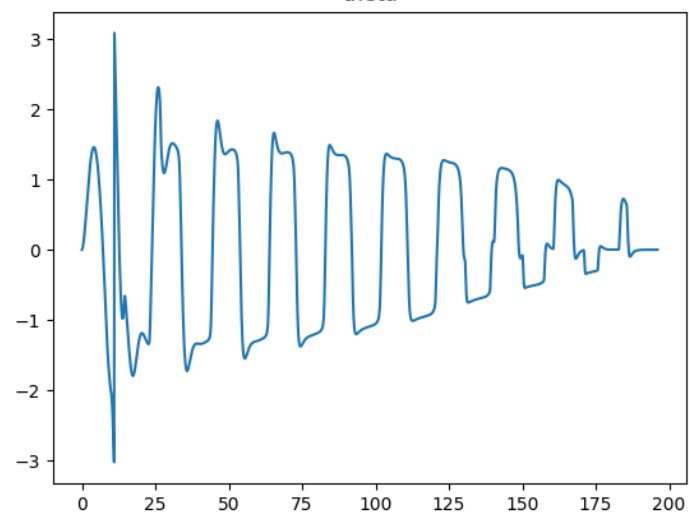


Gain=5, Learning step=0.1, Starting position (0,0,0), Target position (1,1,0)
Simulation

This simulation took 186 seconds.

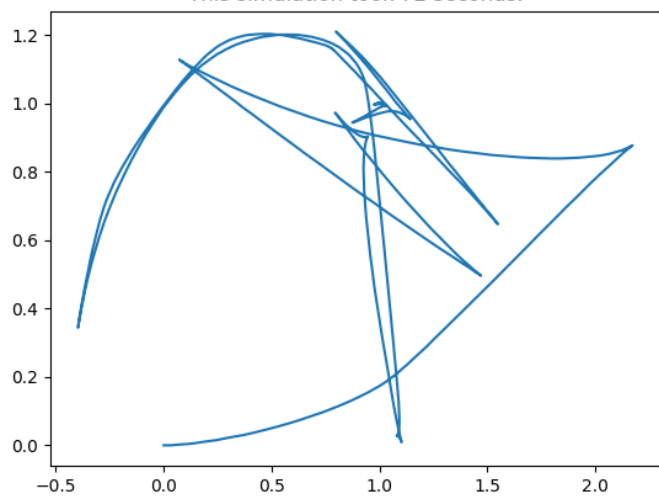


theta

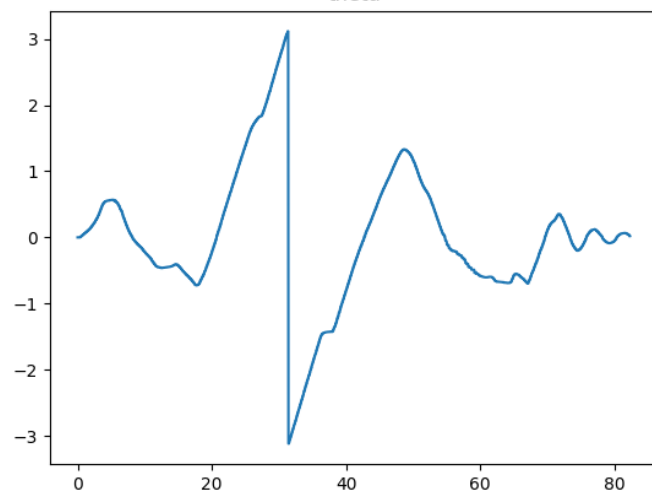


Robot :

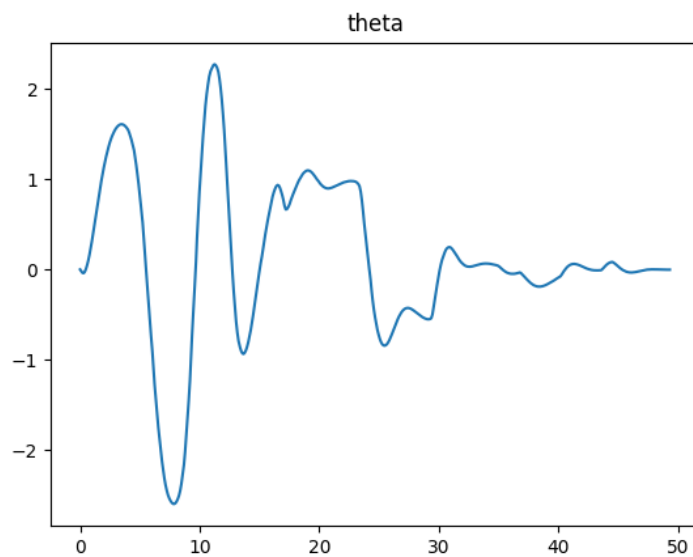
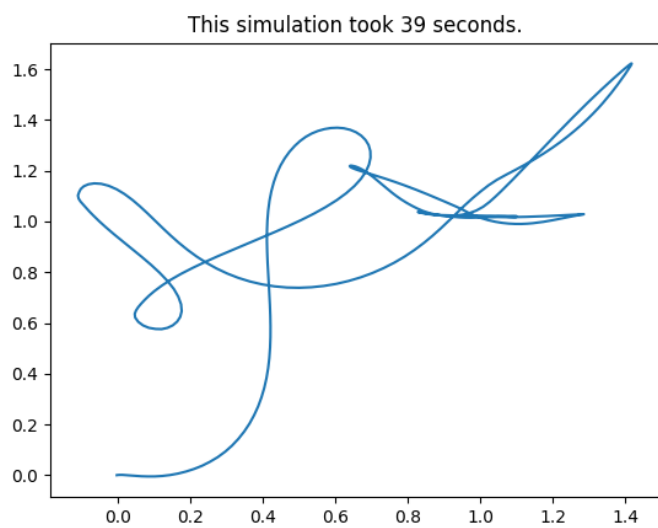
This simulation took 72 seconds.



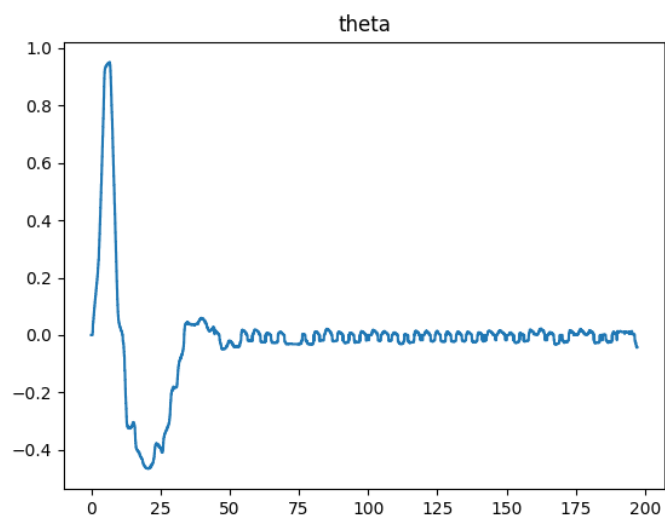
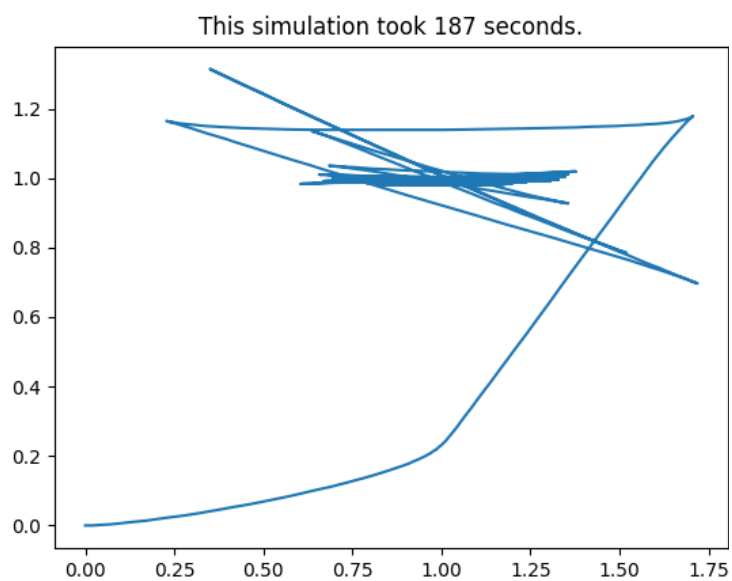
theta



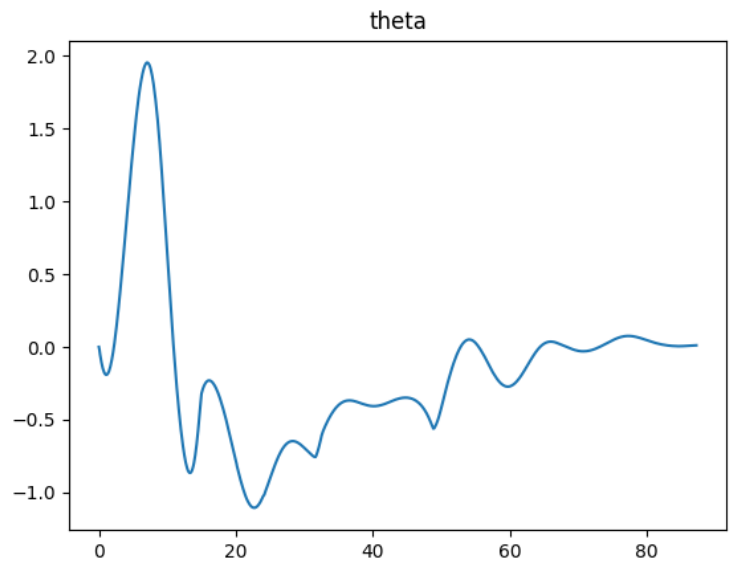
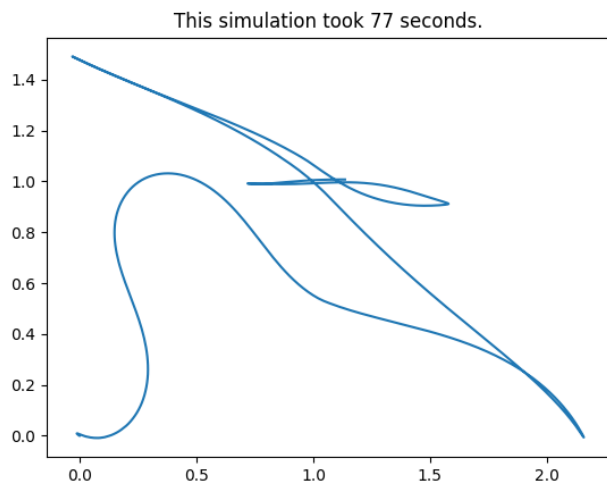
Gain=5, Learning step=0.2, Starting position (0,0,0), Target position (1,1,0)
Simulation



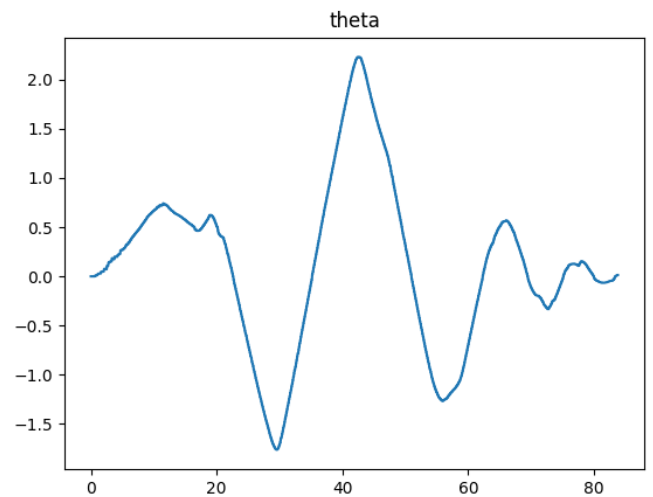
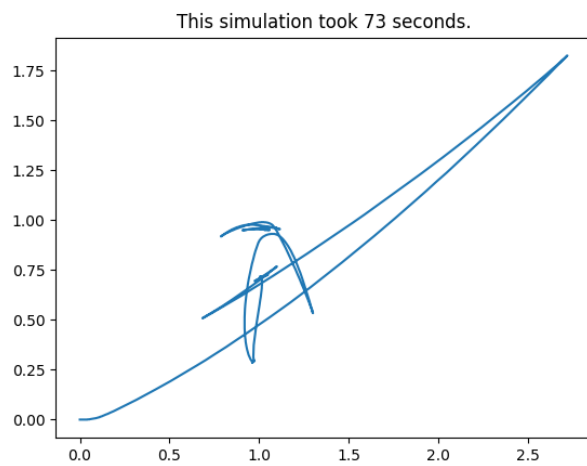
Robot



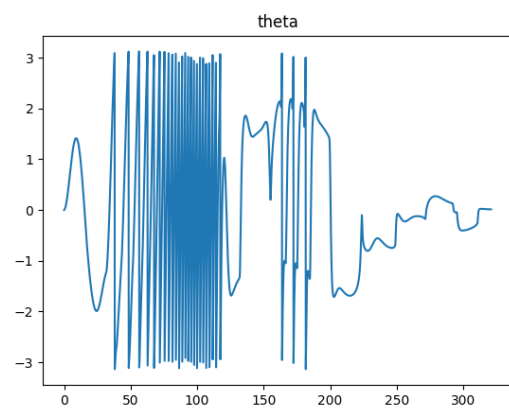
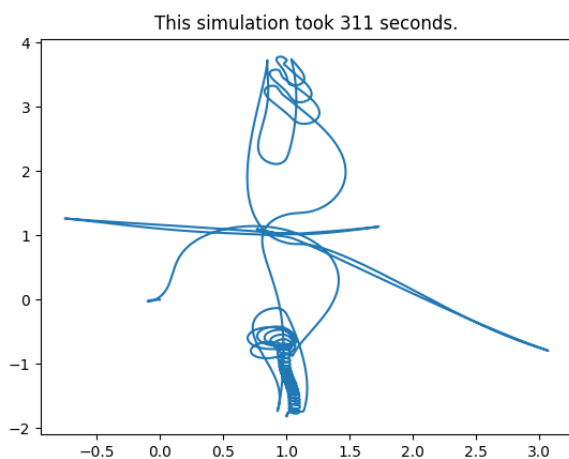
Gain=1, Learning step=0.2, Starting position (0,0,0), Target position (1,1,0)
Simulation



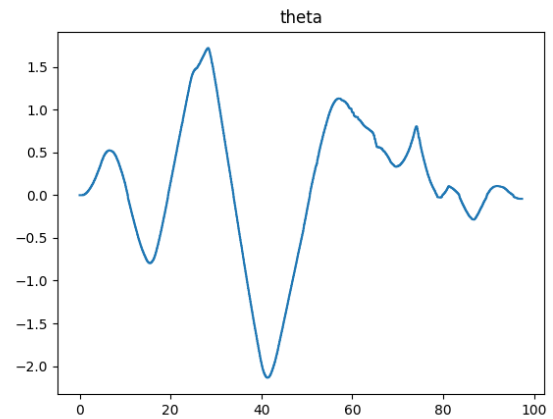
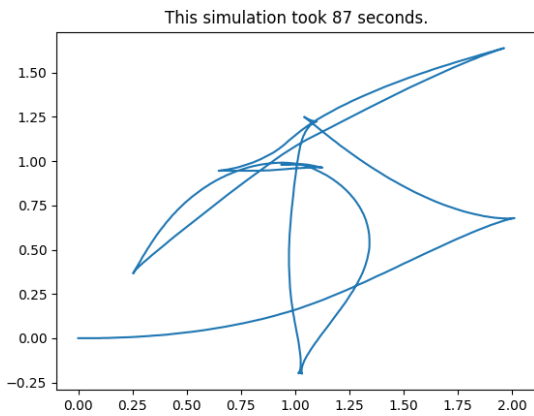
Robot :



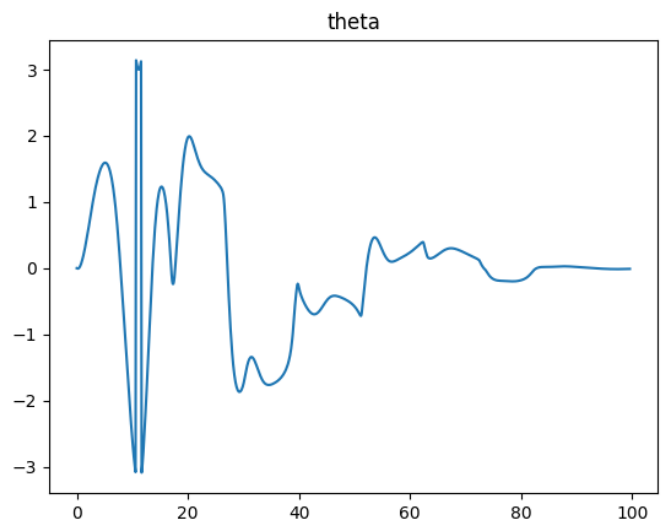
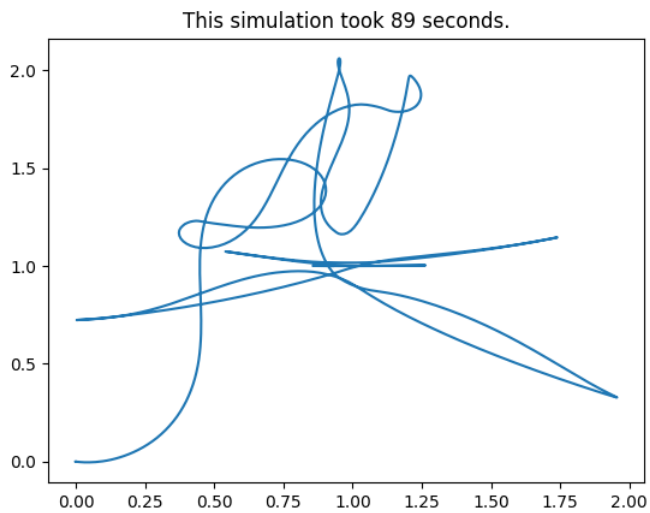
Gain=1, Learning step=0.1, Starting position (0,0,0), Target position (1,1,0)
Simulation



Robot

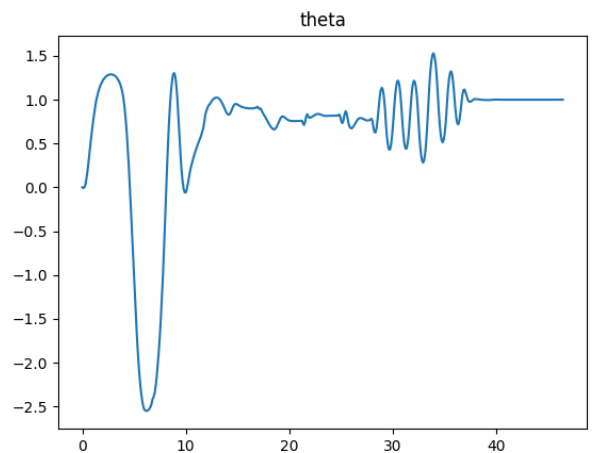
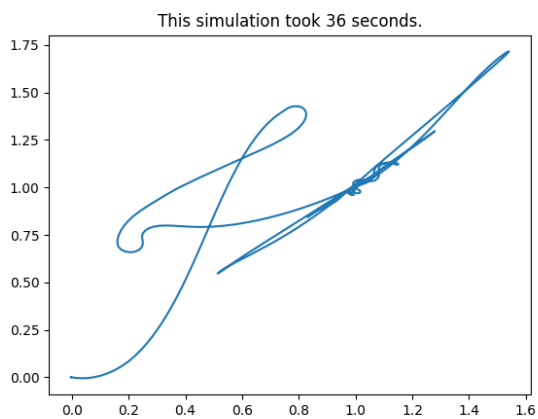


Gain=1, Learning step=0.5, Starting position (0,0,0), Target position (1,1,1)
Simulation

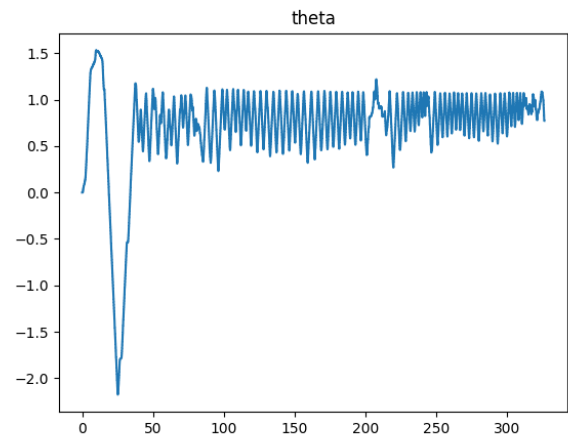
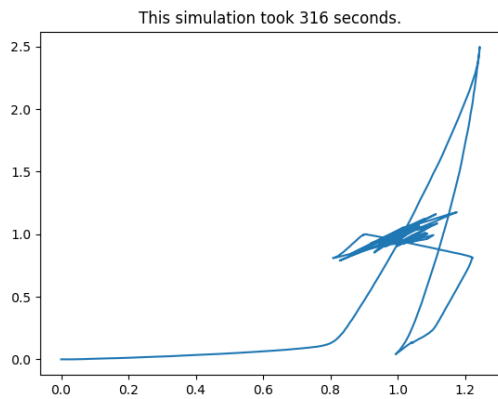


Robot => n'a pas convergé

Gain=5, Learning step=0.5, Starting position (0,0,0), Target position (1,1,1)
simul



robot

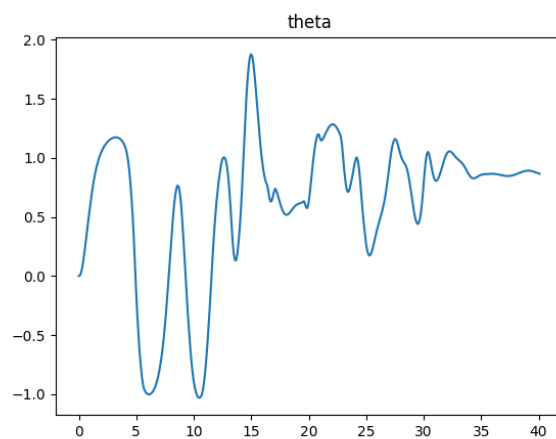
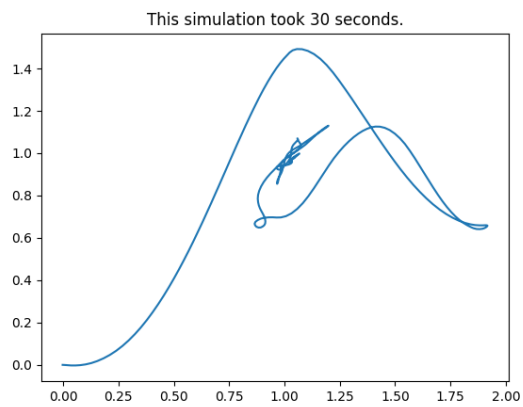


Gain=10, Learning step=0.5, Starting position (0,0,0), Target position (1,1,1)
simulation : ne converge pas

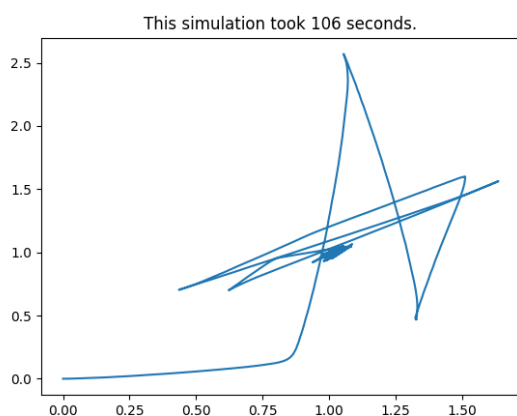
robot : expérience abandonnée, le robot fonce dans le mur

Gain=10, Learning step=0.2, Starting position (0,0,0), Target position (1,1,1)

simulation :

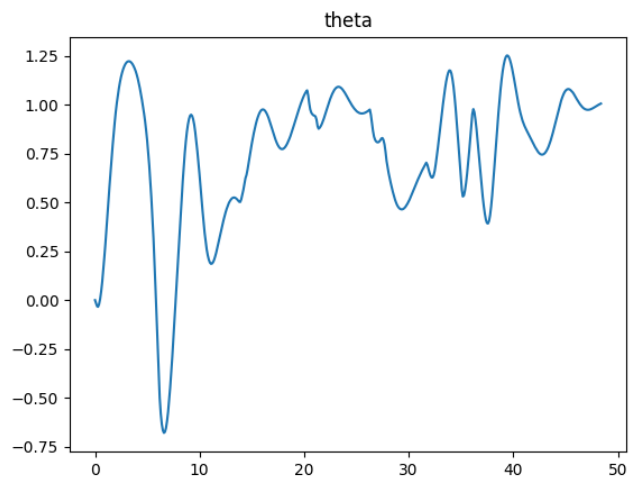
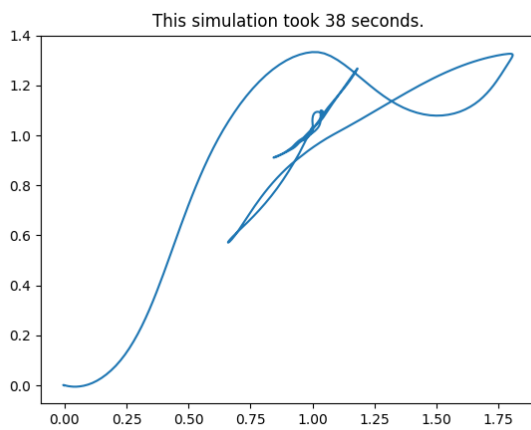
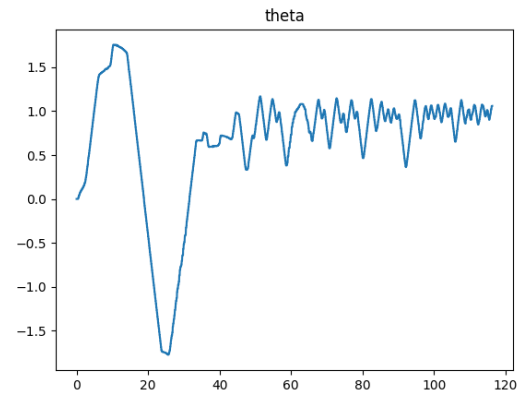


robot



Gain=10, Learning step=0.1, Starting position (0,0,0), Target position (1,1,1)

simul

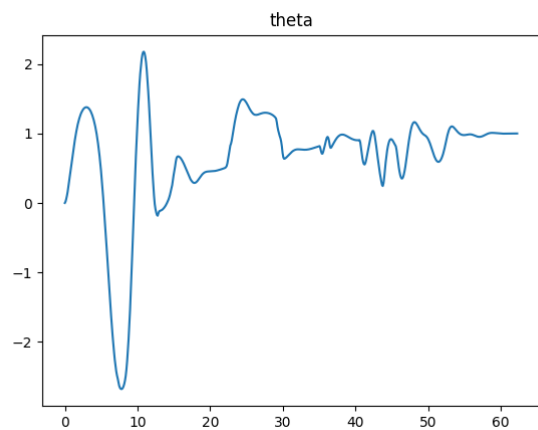
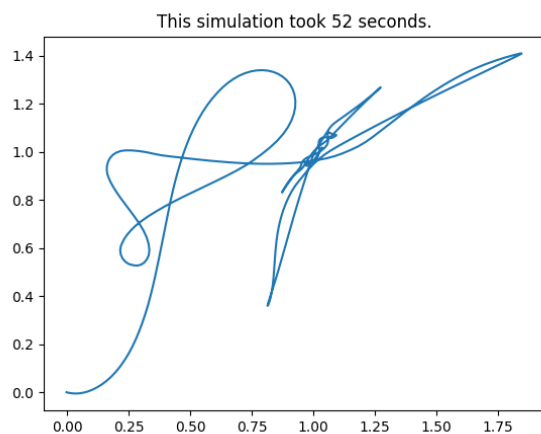


robot

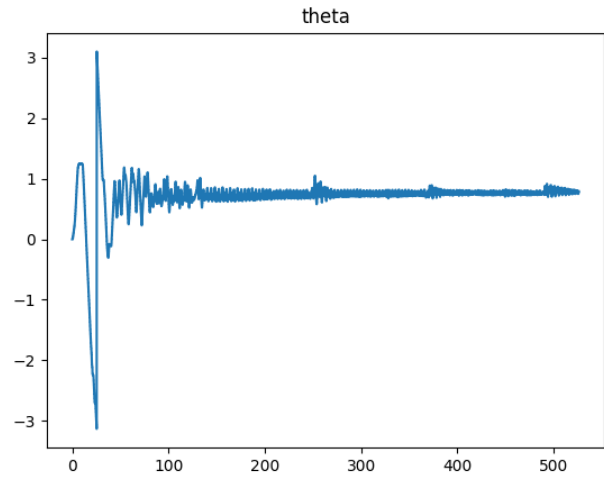
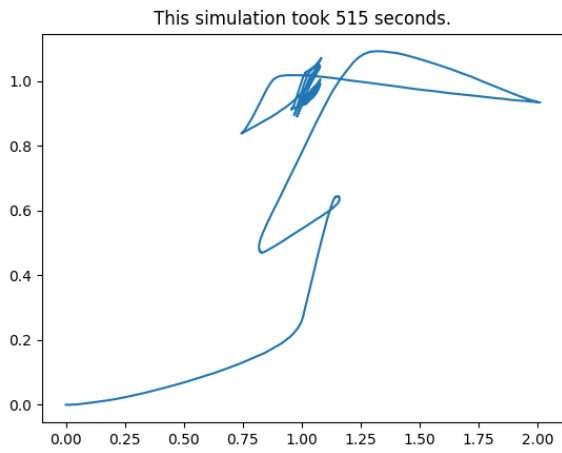
expérience abandonnée : « fonçage de mur »

Gain=5, Learning step=0.2, Starting position (0,0,0), Target position (1,1,1)

simulation



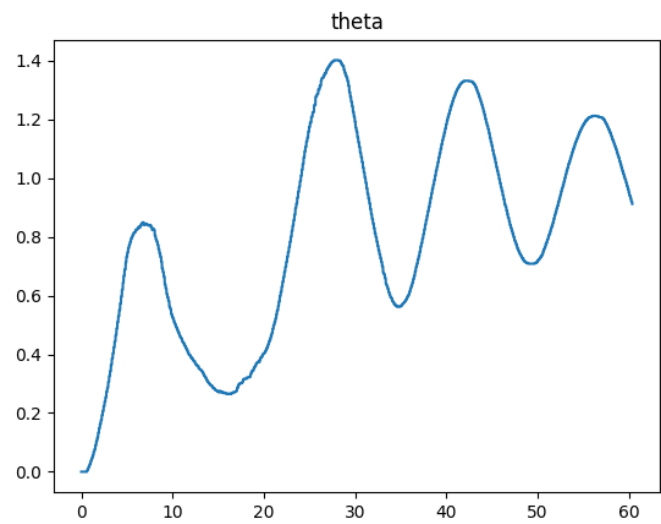
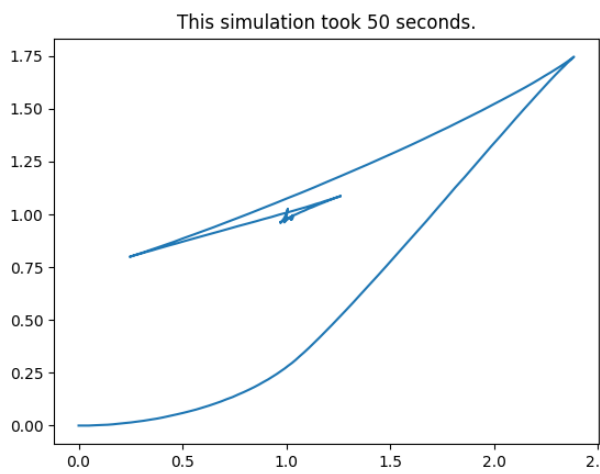
robot



Gain=1, Learning step=0.2, Starting position (0,0,0), Target position (1,1,1)

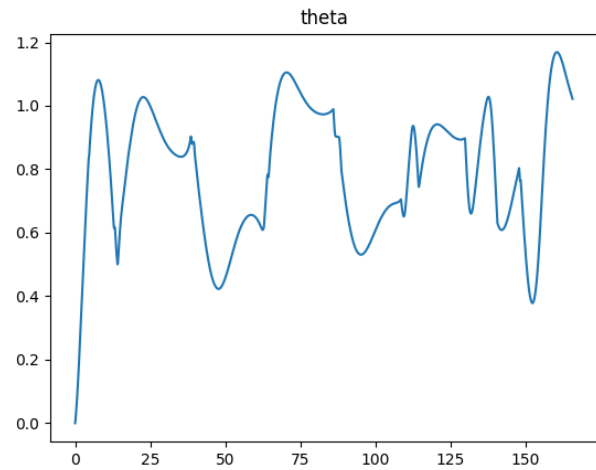
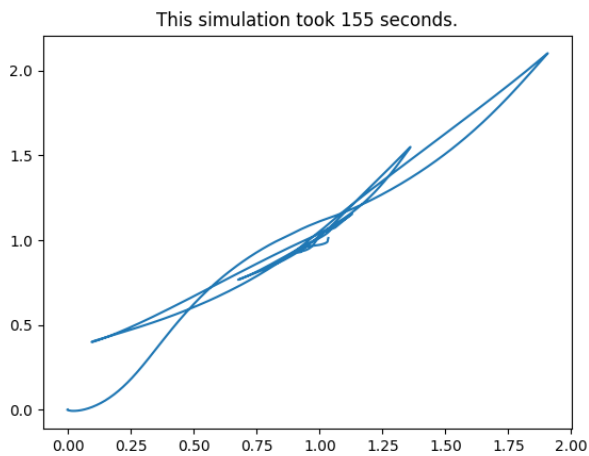
Simulation
n'a pas convergé au bout de 800 secondes

robot



Gain=1, Learning step=0.1, Starting position (0,0,0), Target position (1,1,1)

simulation



robot

