

Socially-Aware Multi-Agent Following with 2D Laser Scans via Deep Reinforcement Learning and Potential Field

Yuxiang Cui, Xiaolong Huang, Yue Wang, Rong Xiong
CSE, Zhejiang University, China

- We propose a potential field based method for formation control and goal assignment.
- We propose a deep model of socially-aware following policy trained by reinforcement learning.
- Our method can be applied to random environments with an arbitrary number of robots.
- We train the policy in a decentralized policy-sharing multi-agent simulation environment.



Real robot evaluation