

Locomotion Control of a Hybrid Propulsion Biomimetic Underwater Vehicle via Deep Reinforcement Learning

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- A novel locomotion control method of biomimetic underwater vehicle (BUV) is proposed based on deep reinforcement learning.
- A hybrid propulsion BUV named RoboDact is presented with two flexible long fins and a double-joint fishtail.
- The feasibility and effectiveness of the proposed control method is demonstrated after extensive comparative simulations.

