

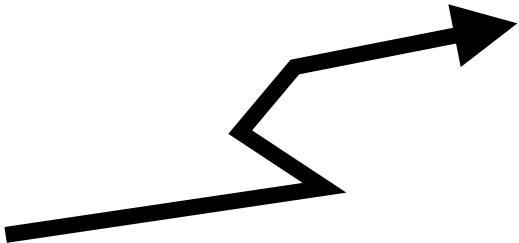


**FCAI**

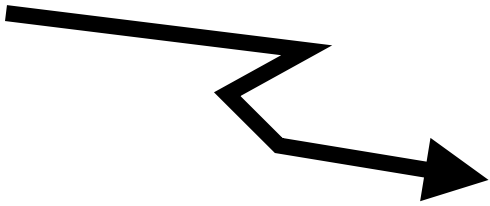
**fcai.fi**

2

3







$a_{0:H}^*$

Iteration 3













# DevM: Decision-time Planning

# Model Predictive Path Integral Control (MPPI)

**Initialise** action sampling distribution  $\{a_t \sim \mathcal{N}(\mu_t, \sigma_t^2)\}_{t=0}^H$

For each iteration

**Sample**  $N$  action sequences  $\{a_{0:H}^i\}_{i=1}^N$

**Evaluate** objective  $J(\mathbf{a}_{0:H}^i, \mathbf{s})$  for each sample

**Select** top  $K$  performing samples

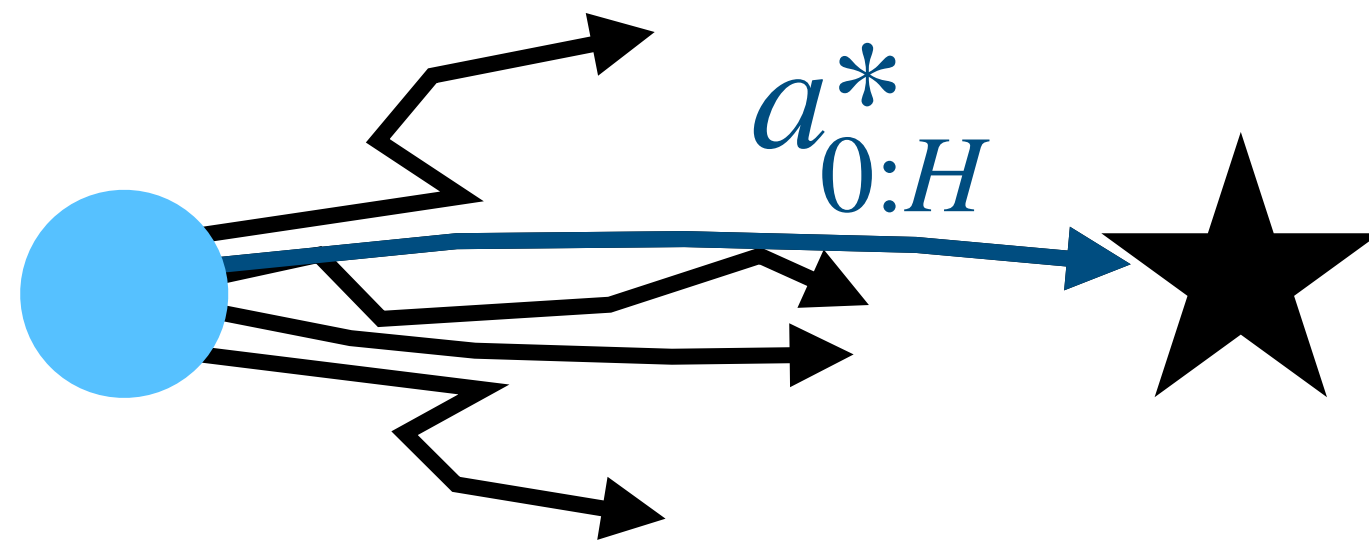
**Update** action distribution parameters  $\{\mu_t, \sigma_t^2\}_{t=0}^H$



# DCWM: Decision-time Planning

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