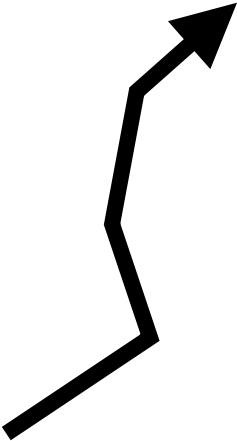
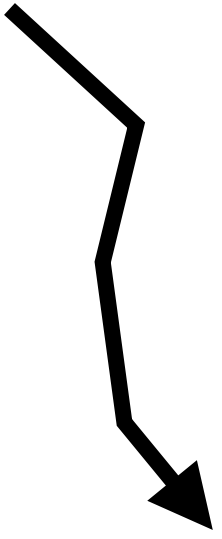


FCAI

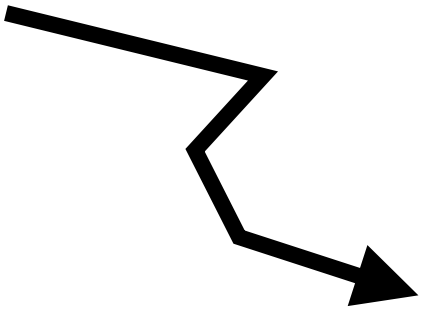
fcai.fi

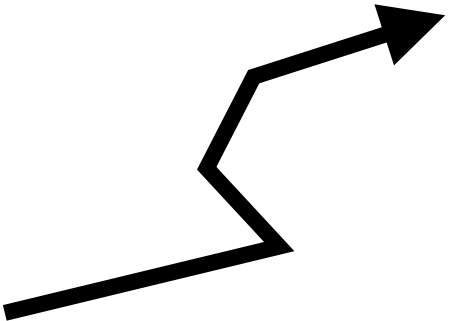




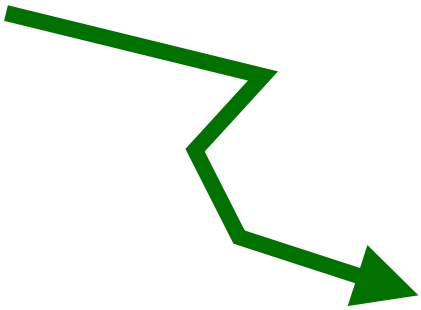


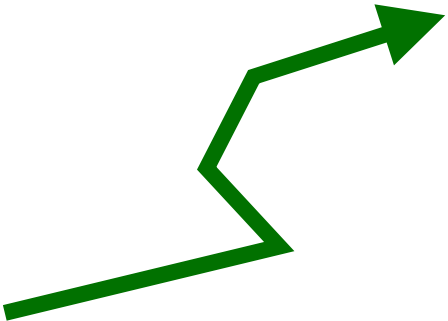














Iteration 2



top-*K*

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

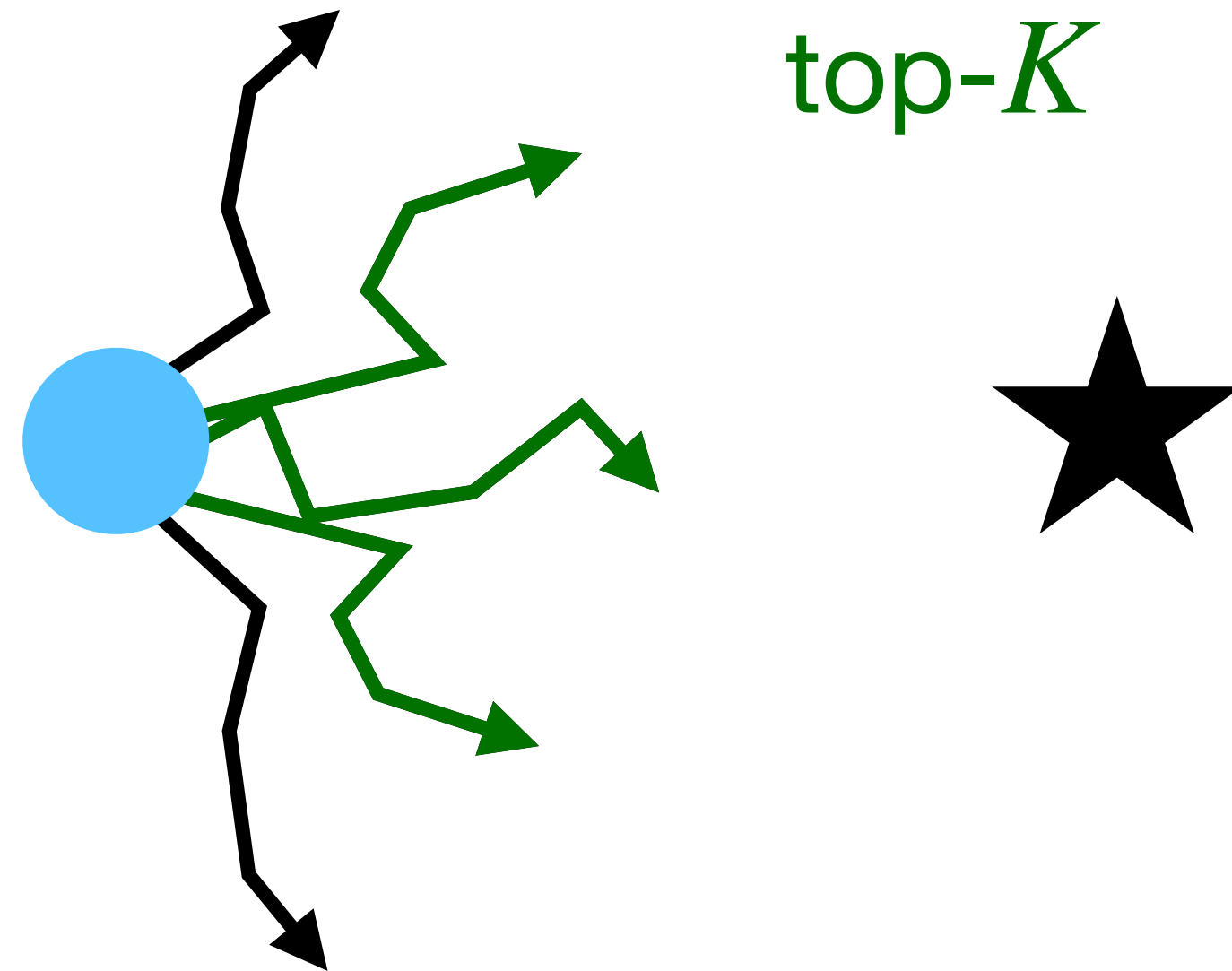
Select top K performing samples

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

DCWM: Decision-time Planning

Model Predictive Path Integral Control (MPPI)

Iteration 2



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

For each iteration

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Select top K performing samples

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DCWM: Decision-time Planning

Model Predictive Path Integral Control (MPPI)

Iteration 3

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 $\{\mu_t, \sigma_t^2\}_{t=0}^H$

