**Your CID Number**

**Coursework 2**

**Description Of Your Implementation**

**High-level summary**

Combination of planning with gradient (Euclidean dist from target) and planning with sampling (cross entropy)

High uncertainty

**Interesting findings and ideas**

Closed loop is computationally heavy, good training reduces the need for it

Based on the idea of knowledge-based intrinsic rewards, I used a training method that encourages actions towards states with high uncertainty