

HyperDrive: Autonomous Self Driving Car in an Urban Setting using Deep Reinforcement Learning

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The Department of Computer Science, National University of Computer and Emerging Sciences, accepts this thesis titled *HyperDrive: Autonomous Self Driving Car in an Urban Setting using Deep Reinforcement Learning*, submitted by Sana Haider (p18-0011), and Syed Asad Zaman (p18-0034), in its current form, and it is satisfying the dissertation requirements for the award of Bachelors Degree in Computer Science.

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Acknowledgements

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Abstract

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Chapter 1

Introduction

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1.1 my section

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Chapter 2

Review of Literature

This chapter provides a comprehensive literature review of the related work to blah blah

Chapter 3

Review of Literature

In the past few years, deep reinforcement learning become a very focus topic due to its success in games like Atari games, GO, and chess. Especially after the success of the project AlphaGO[4] in 2016 and AlphaZero[3] in 2017 by Google DeepMind reinforcement learning become a hot topic. Besides, a fairly recent project known as AlphaFold[1] is used to predict the protein structure has opened doors for reinforcement learning to be applied on more complex real-world problems like goal-oriented autonomous self-driving in a complex dynamic dense environment that includes route planning also. From the review of the following research papers, the authors have concluded that there is not any neural network or reinforcement architecture modeled in CARLA yet that has addressed the problem of route planning in a dynamic dense urban environment

3.1 Reinforcement Learning

When we talked about reinforcement learning it somehow works like human psychology i.e, learning from previous experiences and taking the future action based upon those experiences. In the past, RL was limited to the domain where the features are given to the RL model which was handcrafted or had a low dimensional search space. Due to this limitation, RL wasn't able to be applied to a problem where the search space was limited. For that purpose, a novel artificial agent was designed which was named as **deep**

Q-network (DQN)[2]. This agent has trained on Atari 2600 games. The only input that was provided to this agent was pixels of the game played and the score input. Surprisingly, the agent was able to achieve a professional level of success. DQN was a neural network specifically a deep neural network combined with reinforcement learning whose goal was to maximize the future reward. The limitation of DQN (mentioned in the paper) was that it was limited to Atari games only and didn't apply to games with higher search and state space and to 3D games.

DQN was able to achieve some notable success when it comes to the games where the search space of the possible moves (b^d b is game's breadth and d is depth (game length)) was limited but when it comes to the games where the search space is pretty much large for example Chess ($b = 35, d = 80$) and especially Go ($b = 250, d = 150$) than typical reinforcement learning techniques become exhausted. Another difficulty is in the evaluation of board positions and moves. So to solve the problem of effective search space two general principles can be used:

- Depth of the search can be reduced by position evaluation truncating the tree at state s and replacing the subtree below s .
- Breadth of the search may be reduced by sampling actions from a policy $p(a|s)$ that is a probability distribution over possible moves a in position s .

The approach used for AlphaGo was that a deep neural network was trained on the novel combination of supervised learning from human expert games and for self-play games, reinforcement learning was used. The tree search algorithm that was used in **AlphaGo** was **Monte Carlo Tree Search (MCTS)**. AlphaGo was able to achieve the groundbreaking success of a **99.8% winning rate**. By defeating the European Champion by **5-0** and worldwide champion by **4-1**. This was the first time in the history of a full-sized game of Go that a machine was able to defeat human experts which were almost thought impossible at least for a decade.

Chapter 4

Conclusions and Future Work

conclusions here

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