
Rbased_loss_hc.m

```
function [L, dLdm, dLds, S2] = Rbased_loss_hc(cost, m, s)
```

Input arguments:

cost	cost structure	
.rewardgpmodel	GP to predict reward given state	
m	mean of state distribution	[D x 1]
s	covariance matrix for the state distribution	[D x D]

Output arguments:

L	expected cost	[1 x 1]
dLdm	derivative of expected cost wrt. state mean vector	[1 x D]
dLds	derivative of expected cost wrt. state covariance matrix	[1 x D^2]
S2	variance of cost	[1 x 1]

```
function [L, dLdm, dLds, S2] = Rbased_loss_hc(cost, m, s)
```

Code

```
[L, S2, ~, dLdm, ~, ~, dLds, ~, ~] = gp1d(cost.rewardgpmodel, m, s);
```

```
end
```

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