

Project: Deep RL Arm Manipulation

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1 Abstract

In this project for Deep Reinforcement Arm Manipulation project there were two main objectives in order to complete the goal. These objectives were to create a Deep Q Learning (DQN)¹ agent, which utilizes reward functions(win, loss) in order to teach the robotic arm.

The objectives to achieve the end goal are:

- Have the robotic arm touch an object(green cylinder) with an accuracy of 90% in a minimum 100 runs
- Have the gripper on the robotic arm touch an object(green cylinder) with an accuracy of 80% in a minimum 100 runs

2 Reward Functions

Located in the [ArmPlugin.app](#) file are the reward functions. For both objectives the same arm joint position control was used which is to increase or decrease the joint position. This robot had two joint actions. Also for both objectives the rewards were the same; REWARD_WIN = 0.1f and REWARD_LOSS = -0.1f.

In both objectives the REWARD_LOSS would be given if any of the following factors occurred:

- Robot arm touched the ground
- Robot arm did complete within a time to live(TTL)

For objective 1 if the robotic arm successfully hit the green cylinder it would receive a reward of REWARD_WIN * 5.

However, in objective 2 where the gripper had to hit the green cylinder there needs to be an additional check before giving a reward. After much trial and error there had to be both a REWARD_WIN and REWARD_LOSS on that conditional. Ultimately to achieve this objective REWARD_WIN * 20 a successful gripper touch and REWARD_LOSS * 5 for not.

¹ "Q-learning - Wikipedia." <https://en.wikipedia.org/wiki/Q-learning>. Accessed 29 May. 2018.

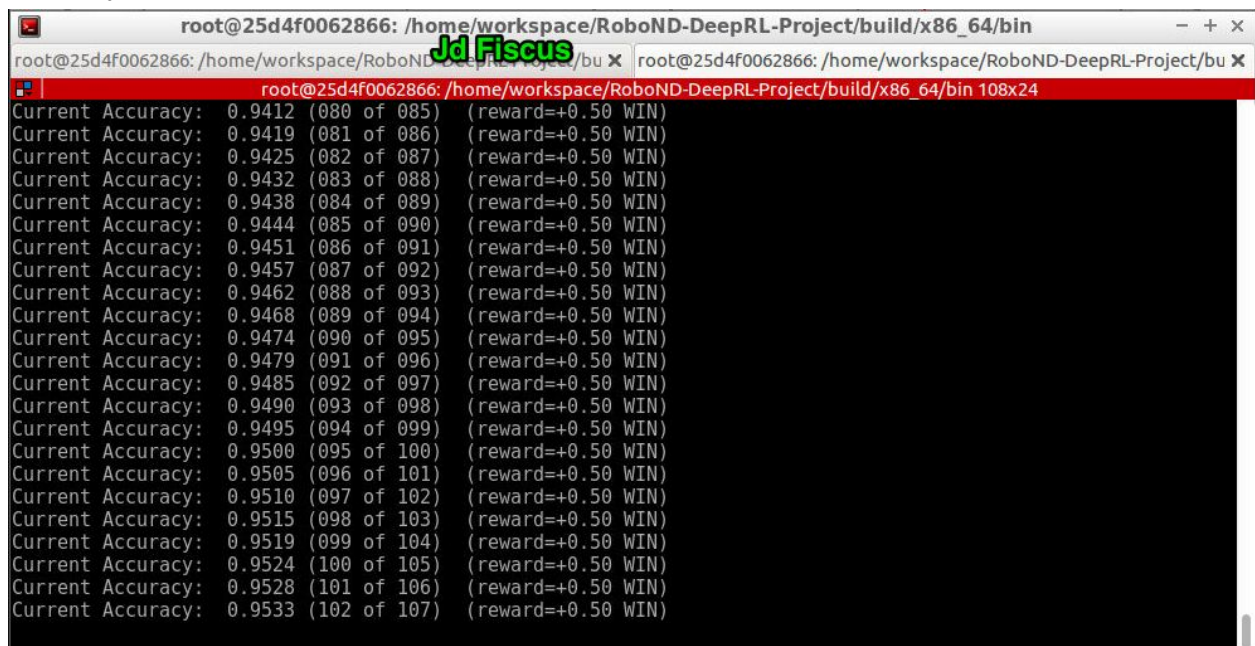
3 Hyper Parameters

It seemed that for both objectives the same hyper parameters were sufficient. Input width and height were set to 64x64. The learning rate was 0.01, a higher replay memory of 20000 was set, and the batch size increased to 512, all helped with learning due to the more complex task.

4 Results

Objective 1

In this objective the goal is to have the robotic arm touch an object(green cylinder) with an accuracy of 90% in a minimum of 100 runs. Below are the successful results:



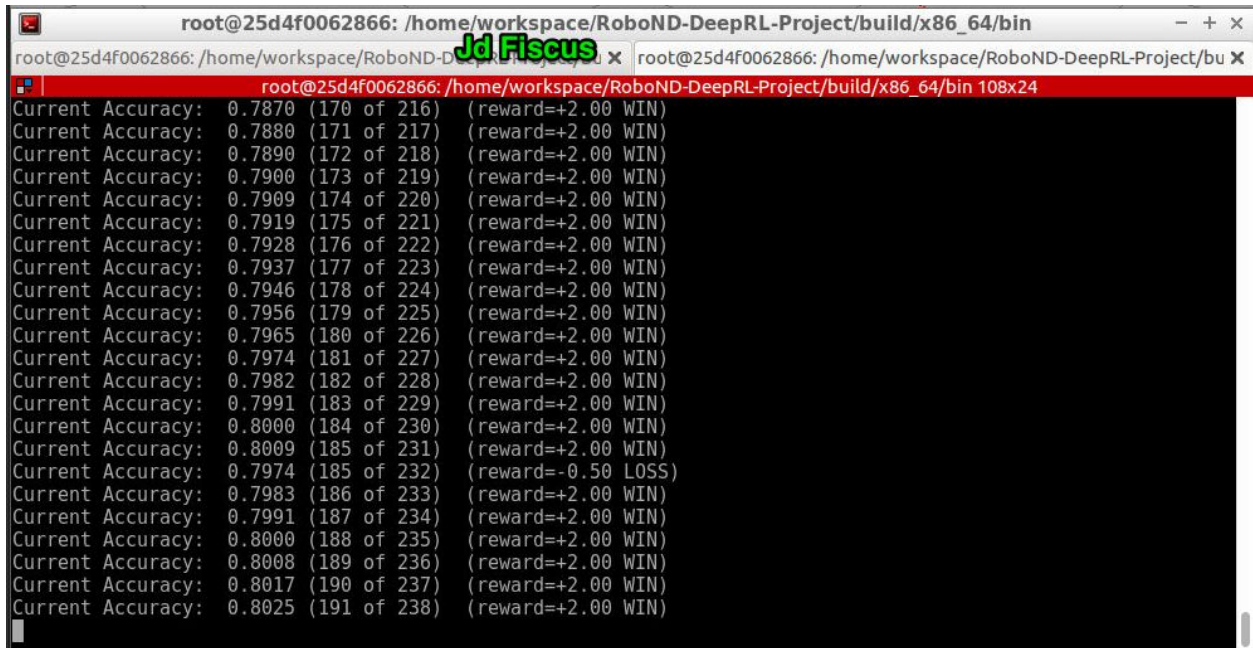
```
root@25d4f0062866: /home/workspace/RoboND-DeepRL-Project/build/x86_64/bin
root@25d4f0062866: /home/workspace/RoboND-DeepRL-Project/build/x86_64/bin 108x24
Current Accuracy: 0.9412 (080 of 085) (reward=+0.50 WIN)
Current Accuracy: 0.9419 (081 of 086) (reward=+0.50 WIN)
Current Accuracy: 0.9425 (082 of 087) (reward=+0.50 WIN)
Current Accuracy: 0.9432 (083 of 088) (reward=+0.50 WIN)
Current Accuracy: 0.9438 (084 of 089) (reward=+0.50 WIN)
Current Accuracy: 0.9444 (085 of 090) (reward=+0.50 WIN)
Current Accuracy: 0.9451 (086 of 091) (reward=+0.50 WIN)
Current Accuracy: 0.9457 (087 of 092) (reward=+0.50 WIN)
Current Accuracy: 0.9462 (088 of 093) (reward=+0.50 WIN)
Current Accuracy: 0.9468 (089 of 094) (reward=+0.50 WIN)
Current Accuracy: 0.9474 (090 of 095) (reward=+0.50 WIN)
Current Accuracy: 0.9479 (091 of 096) (reward=+0.50 WIN)
Current Accuracy: 0.9485 (092 of 097) (reward=+0.50 WIN)
Current Accuracy: 0.9490 (093 of 098) (reward=+0.50 WIN)
Current Accuracy: 0.9495 (094 of 099) (reward=+0.50 WIN)
Current Accuracy: 0.9500 (095 of 100) (reward=+0.50 WIN)
Current Accuracy: 0.9505 (096 of 101) (reward=+0.50 WIN)
Current Accuracy: 0.9510 (097 of 102) (reward=+0.50 WIN)
Current Accuracy: 0.9515 (098 of 103) (reward=+0.50 WIN)
Current Accuracy: 0.9519 (099 of 104) (reward=+0.50 WIN)
Current Accuracy: 0.9524 (100 of 105) (reward=+0.50 WIN)
Current Accuracy: 0.9528 (101 of 106) (reward=+0.50 WIN)
Current Accuracy: 0.9533 (102 of 107) (reward=+0.50 WIN)
```

[Video](#)

For this objective the robotic arm seemed to learn quick and there were very little loss rewards. However on the times it did fail it was either hitting the ground, or struggling in the TTL. Also there was a behavior were it would get a successful result but launch the cylinder off screen.

Objective 2

In the second objective the goal is to have the gripper on the robotic arm touch an object(green cylinder) with an accuracy of 80% in a minimum of 100 runs.



```
root@25d4f0062866: /home/workspace/RoboND-DeepRL-Project/build/x86_64/bin
root@25d4f0062866: /home/workspace/RoboND-DeepRL-Project/build/x86_64/bin 108x24
Current Accuracy: 0.7870 (170 of 216) (reward=+2.00 WIN)
Current Accuracy: 0.7880 (171 of 217) (reward=+2.00 WIN)
Current Accuracy: 0.7890 (172 of 218) (reward=+2.00 WIN)
Current Accuracy: 0.7900 (173 of 219) (reward=+2.00 WIN)
Current Accuracy: 0.7909 (174 of 220) (reward=+2.00 WIN)
Current Accuracy: 0.7919 (175 of 221) (reward=+2.00 WIN)
Current Accuracy: 0.7928 (176 of 222) (reward=+2.00 WIN)
Current Accuracy: 0.7937 (177 of 223) (reward=+2.00 WIN)
Current Accuracy: 0.7946 (178 of 224) (reward=+2.00 WIN)
Current Accuracy: 0.7956 (179 of 225) (reward=+2.00 WIN)
Current Accuracy: 0.7965 (180 of 226) (reward=+2.00 WIN)
Current Accuracy: 0.7974 (181 of 227) (reward=+2.00 WIN)
Current Accuracy: 0.7982 (182 of 228) (reward=+2.00 WIN)
Current Accuracy: 0.7991 (183 of 229) (reward=+2.00 WIN)
Current Accuracy: 0.8000 (184 of 230) (reward=+2.00 WIN)
Current Accuracy: 0.8009 (185 of 231) (reward=+2.00 WIN)
Current Accuracy: 0.7974 (185 of 232) (reward=-0.50 LOSS)
Current Accuracy: 0.7983 (186 of 233) (reward=+2.00 WIN)
Current Accuracy: 0.7991 (187 of 234) (reward=+2.00 WIN)
Current Accuracy: 0.8000 (188 of 235) (reward=+2.00 WIN)
Current Accuracy: 0.8008 (189 of 236) (reward=+2.00 WIN)
Current Accuracy: 0.8017 (190 of 237) (reward=+2.00 WIN)
Current Accuracy: 0.8025 (191 of 238) (reward=+2.00 WIN)
```

This objective was more difficult to train, which seemed to take a lot of trial and error. The first issue that happened was the robotic arm seemed to consistently fail on TTL. Then it started to get some successful rewards. However, still it would run into problems hitting the cylinder with its arm by over extending or under extending and hitting the floor. Finally, it seemed to get to the objectives goal.

5 Future Work

There seems to be some fine tuning that could be done in order to increase the learning rate. This could possibly be done with better reward functions. Understanding the amount of pressure the joint is moving once the arm touching the cylinder could also help. Finally, the most repeatable issue was the fail with TTL. To fix TTL it would be beneficial to increase the live time.