Master Thesis

Jonas Jakubassa

January 22, 2024

Contents

1	Introduction							7									
	1.1	Theore	etical Background .														7
			Statistical Theory														

4 CONTENTS

List of Figures

Chapter 1

Introduction

[1, p. 275] claims something. Here is some other claim [2, 3]. This is supported by [4]

1.1 Theoretical Background

1.1.1 Statistical Theory

The real function f on D is continuous in the point $x \in D$, if for every $\epsilon > 0$ there exists $\delta > 0$ such that

$$\forall y \in D \text{ with } |x - y| < \delta \Longrightarrow |f(x) - f(y)| < \epsilon.$$

Name	Departement	Salary
John Connor	Costumer Service	10'000
Brain	R & D	50'000
Malcolm	Management	200'000

Table 1.1: The employees with their salaries from company XY

Bibliography

- [1] J. Eßer, N. Bach, C. Jestel, O. Urbann, and S. Kerner, "Guided Reinforcement Learning: A Review and Evaluation for Efficient and Effective Real-World Robotics [Survey]," *IEEE Robotics & Automation Magazine*, vol. 30, pp. 67–85, June 2023.
- [2] D. Helbing and P. Molnár, "Social force model for pedestrian dynamics," *Physical Review E*, vol. 51, pp. 4282–4286, May 1995.
- [3] X. Lu, H. Woo, A. Faragasso, A. Yamashita, and H. Asama, "Socially aware robot navigation in crowds via deep reinforcement learning with resilient reward functions," *Advanced Robotics*, vol. 36, pp. 388–403, Apr. 2022.
- [4] C. Chen, Y. Liu, S. Kreiss, and A. Alahi, "Crowd-Robot Interaction: Crowd-Aware Robot Navigation With Attention-Based Deep Reinforcement Learning," in 2019 International Conference on Robotics and Automation (ICRA), (Montreal, QC, Canada), pp. 6015–6022, IEEE, May 2019.