CS 237B: Principles of Robot Autonomy II

Problem Set 01

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**Problem 1: Markovian Drone**

(ii) Heatmap of the optimal value function:

Uma imagem contendo Tabela

Descrição gerada automaticamente

Figure - Optimal Value Function

(iv) Heatmap policy and drone trajectory (Used a customized function from scratch) the highlighted squares indicate the drone trajectory:

Gráfico

Descrição gerada automaticamente com confiança média

Figure 2 - Policy heatmap.

The policy evaluates the trajectory to the goal point maximizing the reward, avoiding the storm, taking the shortest path possible in that way.

(vi) Bellman Equation of the optimal Q-function (Q-network optimization):

Where:

* : Boolean (1) if is a terminal state, reducing the equation to - .

(ix) My example will be given in the Nuclear area: In Nuclear Power Plant we have a group of variables to control the Reactor – Coolant average Temperature, Axial power distributions, Pressure on secondary side. The behavior of these set of variables generates control commands to move the control bar in/out of the Reactor Vessel. We have a historical set of these variable behaviors and actions, so we could train a Q-network with these historical samples and evaluate the results in a nuclear reactor control.

(x)

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| --- | --- |
| Tabela  Descrição gerada automaticamente com confiança baixa  Figure – learning rate = 1e-4. | Tabela  Descrição gerada automaticamente com confiança baixa  Figure - learning rate = 1e-3. |
| Uma imagem contendo Tabela  Descrição gerada automaticamente  Figure - learning rate = 1e-2. | Gráfico  Descrição gerada automaticamente com confiança média  Figure - learning rate = 1e-1. |

**Problem 2: Classification and Sliding Window Detection**

**Image Classification**

(iv) Tensor Board Model Structure:

* dimension of each “bottleneck” image: [?, 2048]
* parameters (weights + biases) are we optimizing:

(v) We could have problem with overfitting when evaluate the training process. And probably need to use a dropout layer to avoid it.

**Object Detection and Localization**

(viii) Detection plot:

Interface gráfica do usuário

Descrição gerada automaticamente

Figure 7 - Sliding Window Classification

(ix) Convolutional layer (mixed\_10)

Operation – Convolutional 2D sliding.

Feature vector calculation process -

(xiii) Results:

|  |  |  |
| --- | --- | --- |
| Tela de computador  Descrição gerada automaticamente  Figure 8 - Saliency for class 'cat'. | Uma imagem contendo Interface gráfica do usuário  Descrição gerada automaticamente  Figure 9 - Saliency for class 'dog'. | Interface gráfica do usuário  Descrição gerada automaticamente com confiança média  Figure 10 - Saliency for class 'neg'. |