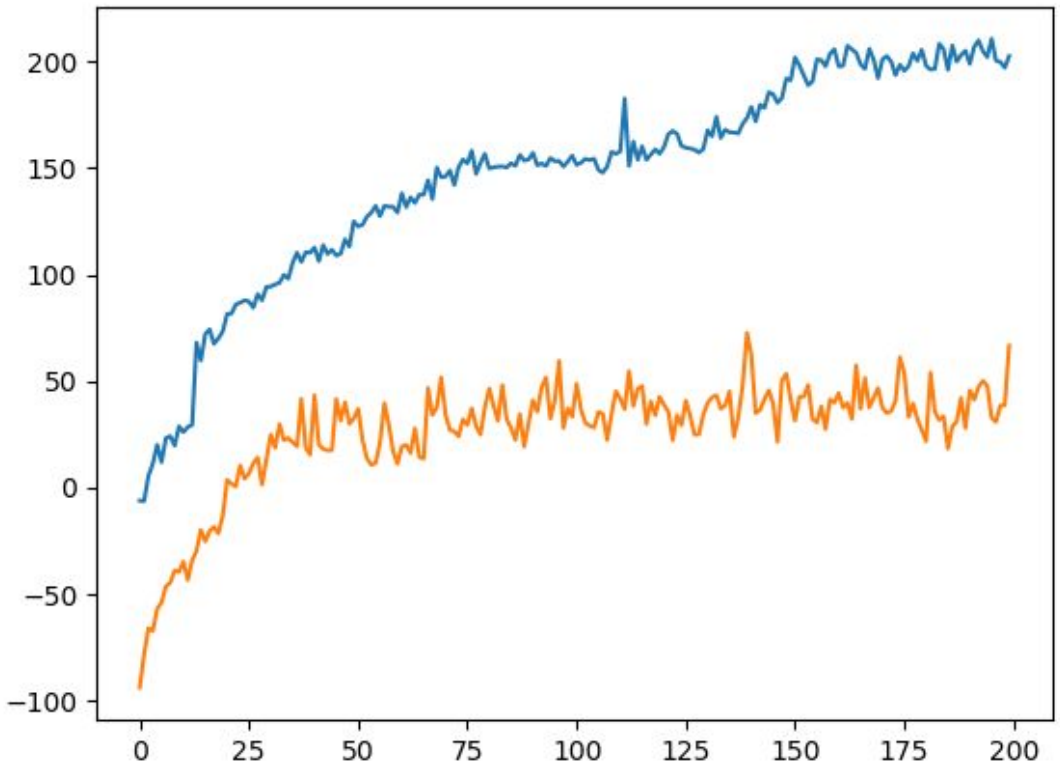
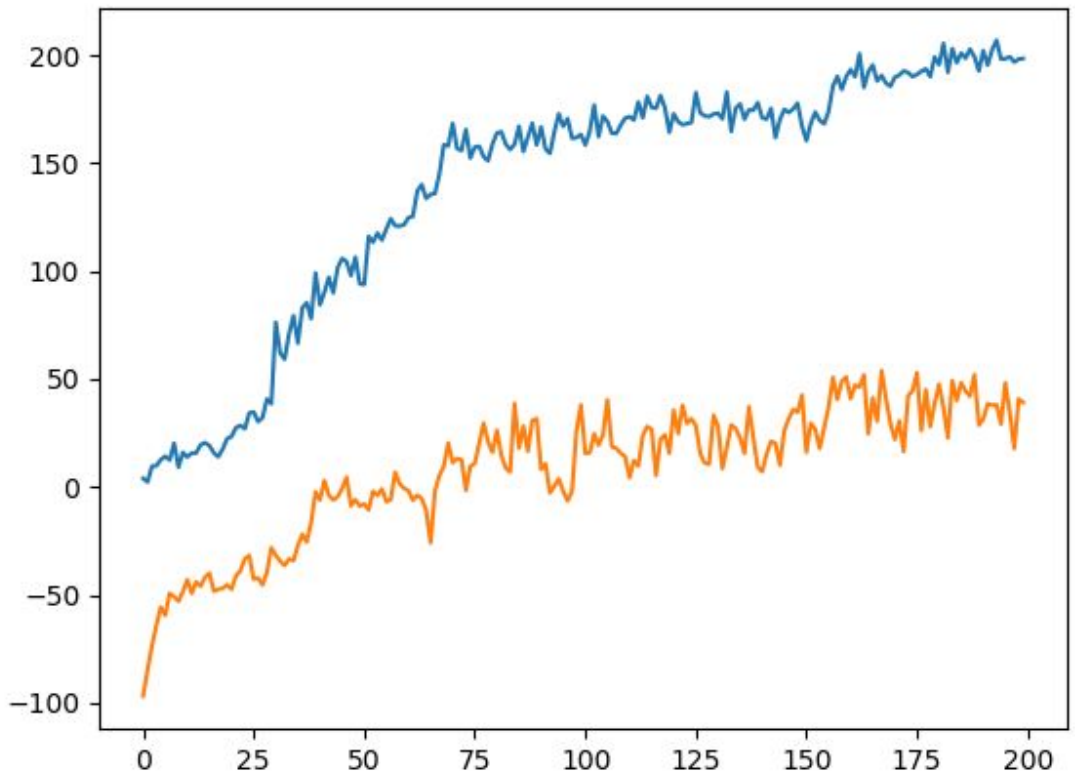
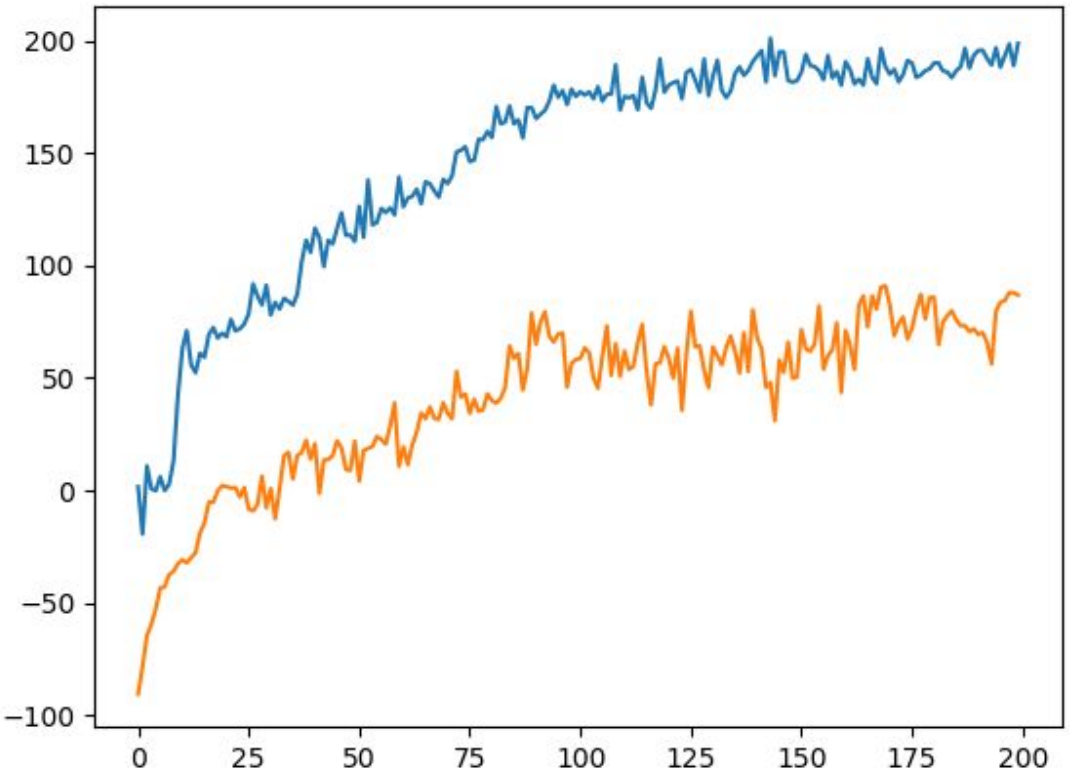
cross: 0.98,
mutation: 0.02,
select: 10,
num_iter: 1000,
gen_size: 100,
num_generations: 200



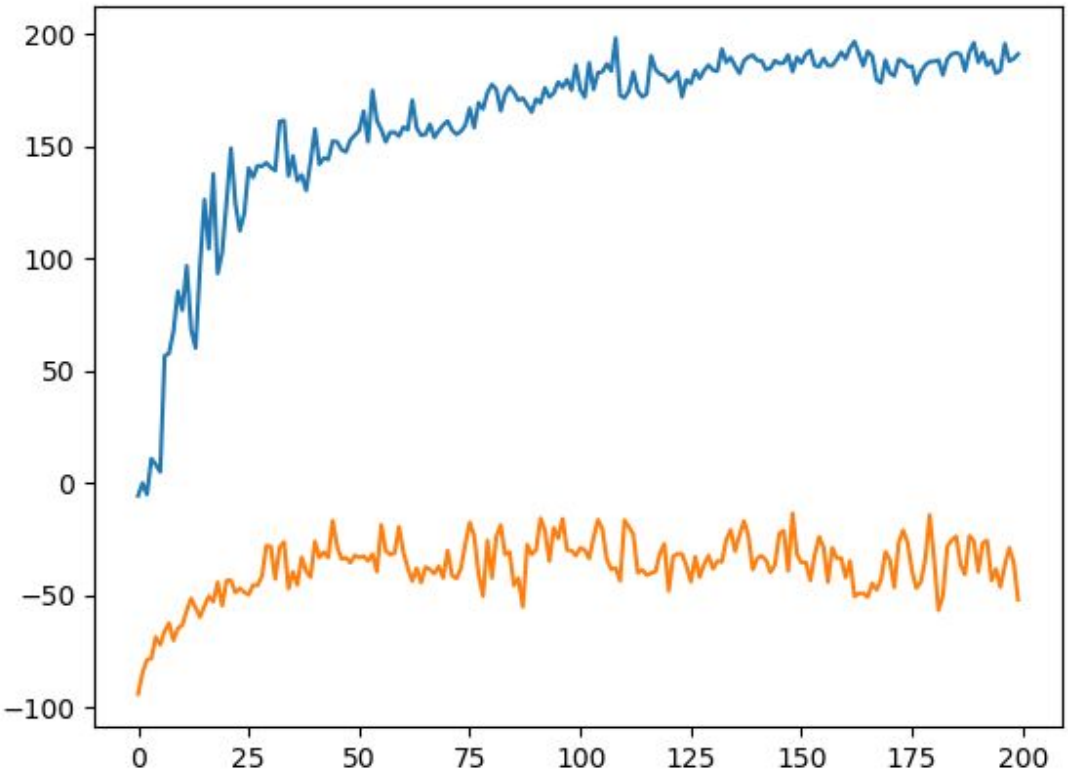
cross: 0.98,
mutation: 0.02,
select: 3,
num_iter: 1000,
gen_size: 100,
num_generations: 200



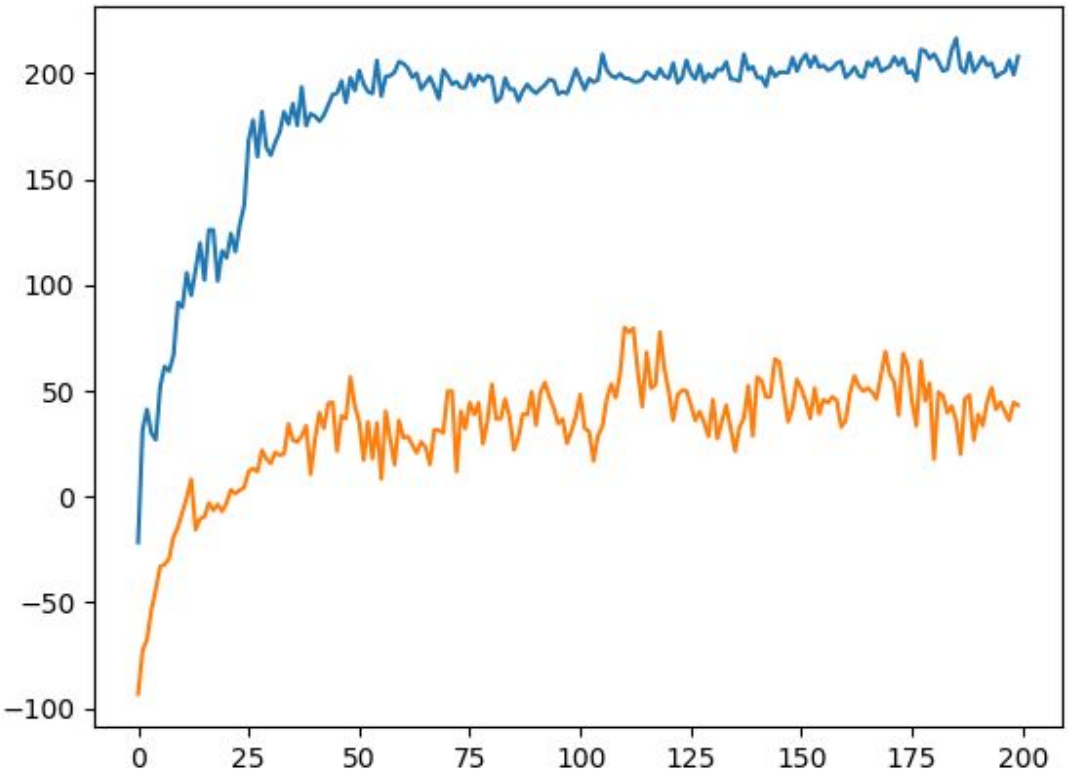
cross: 0.98,
mutation: 0.02,
select: 30,
num_iter: 1000,
gen_size: 100,
num_generations: 200



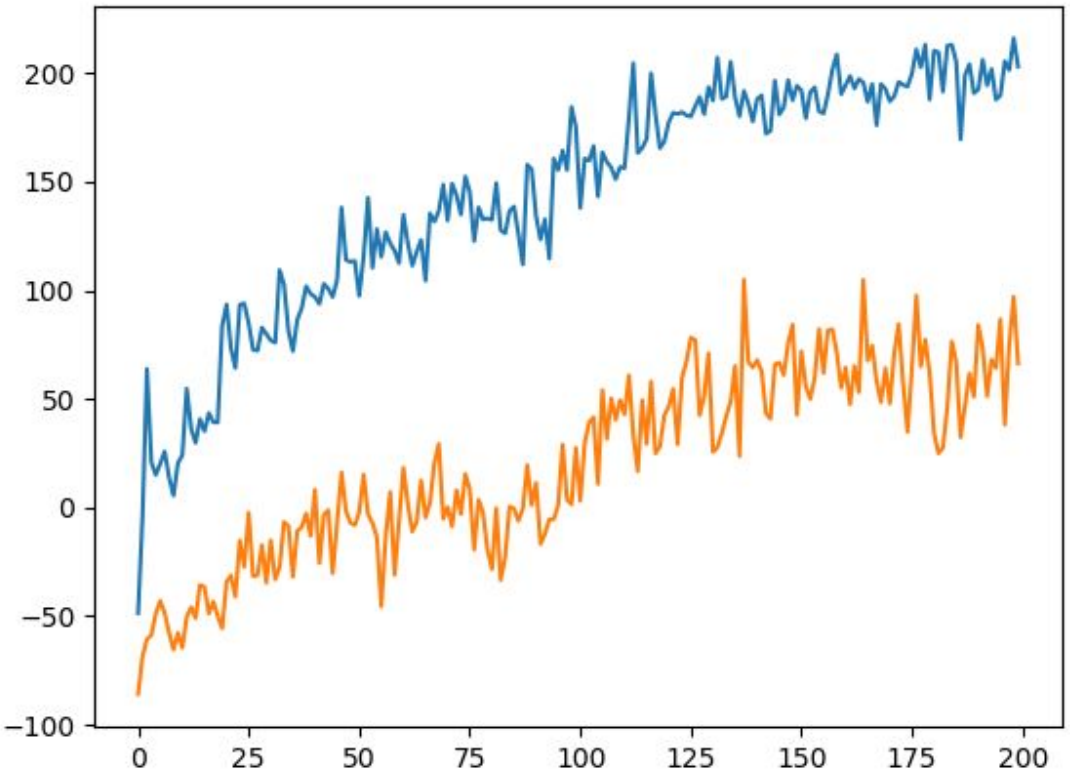
cross: 0.98,
mutation: 0.1,
select: 10,
num_iter: 1000,
gen_size: 100,
num_generations: 200



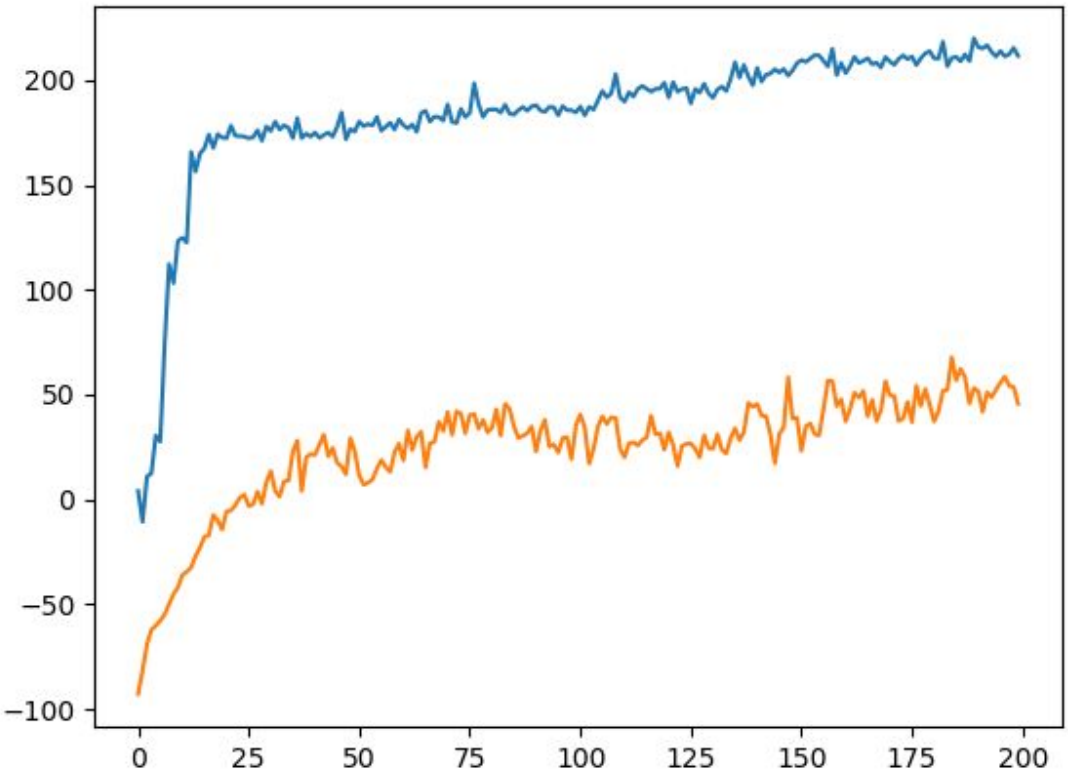
cross: 0.85,
mutation: 0.02,
select: 10,
num_iter: 1000,
gen_size: 100,
num_generations: 200



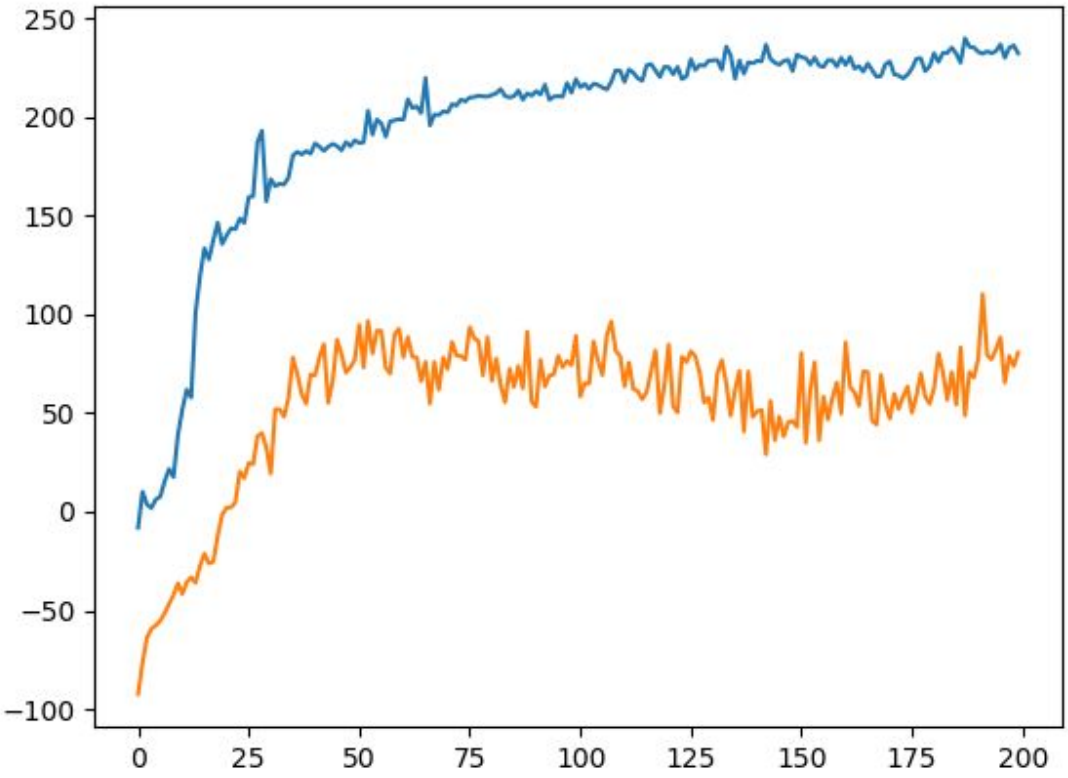
cross: 0.98,
mutation: 0.02,
select: 10,
num_iter: 1000,
gen_size: 30,
num_generations: 200



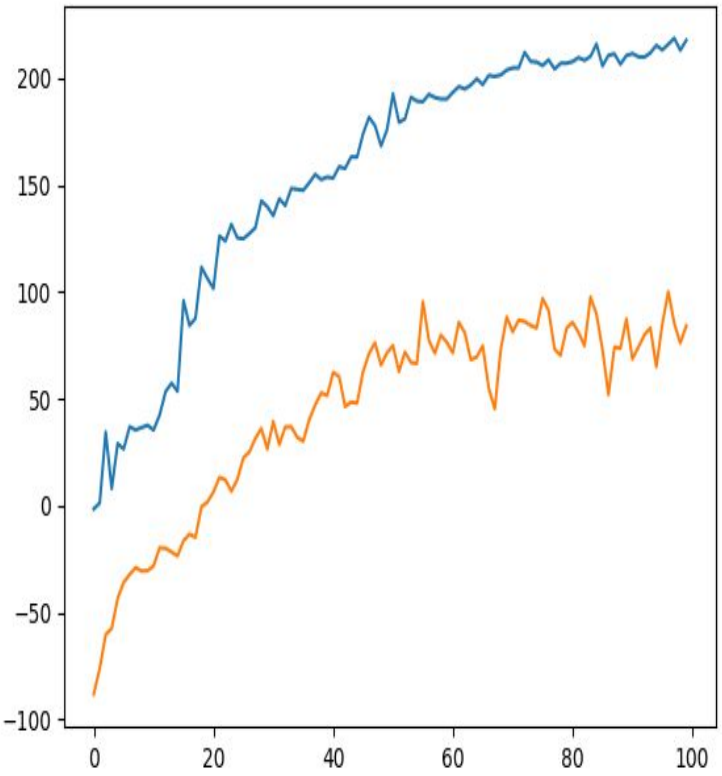
cross: 0.98,
mutation: 0.02,
select: 10,
num_iter: 1000,
gen_size: 300,
num_generations: 200



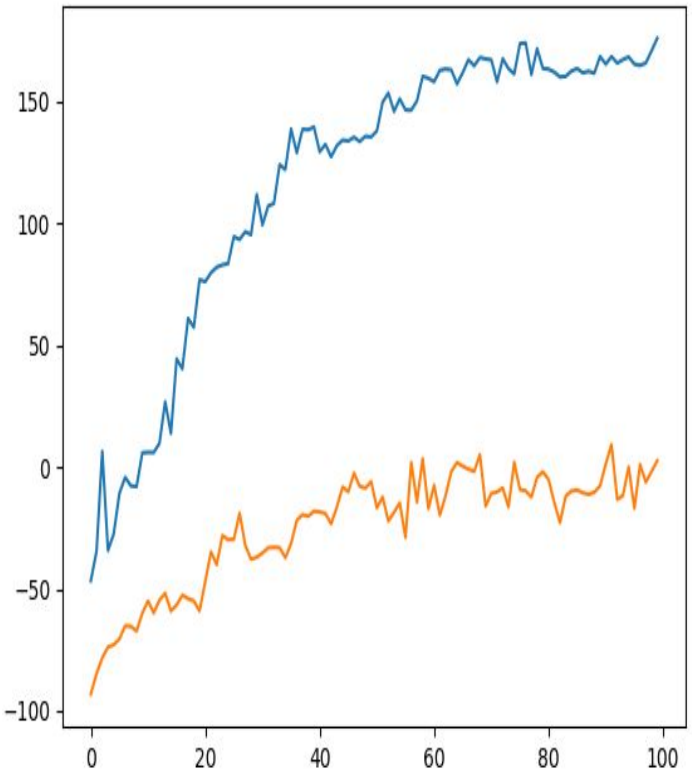
cross: 0.98,
mutation: 0.02,
select: 10,
num_iter: 3000,
gen_size: 100,
num_generations: 200



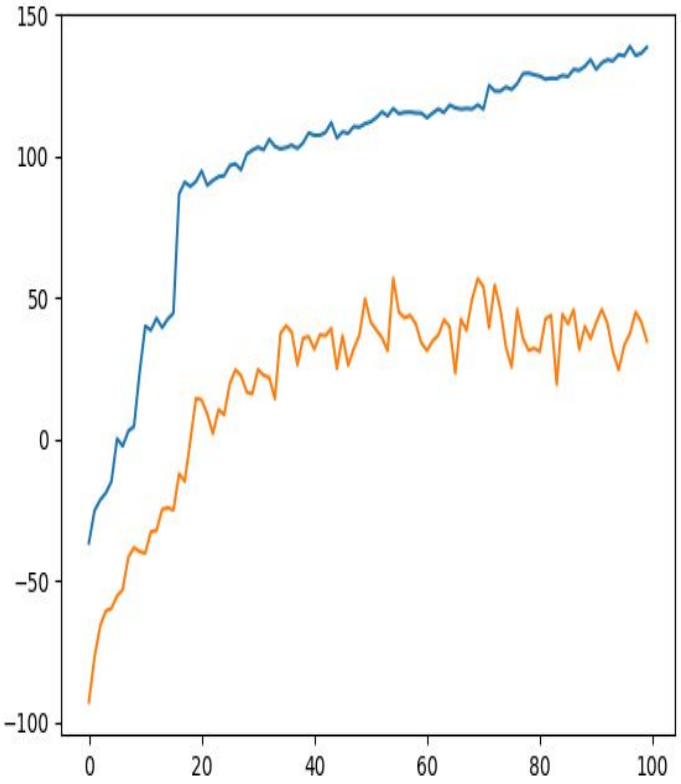
cross: 0.98
mutation: 0.02
select: 10
num_iter: 1000
gen_size: 100
num_generations: 100
num_repeat: 5



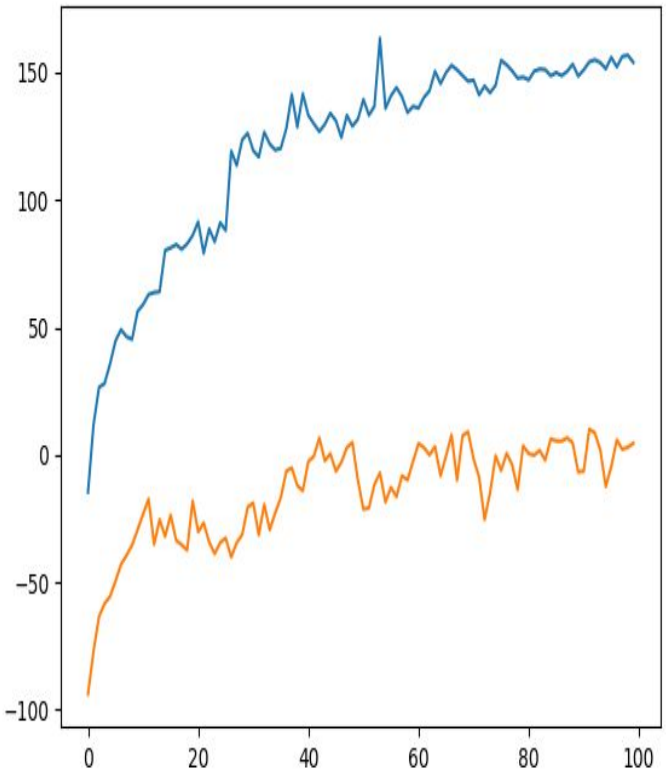
cross: 0.85
mutation: 0.08
select: 10
num_iter: 1000
gen_size: 100
num_generations: 100
num_repeat: 5



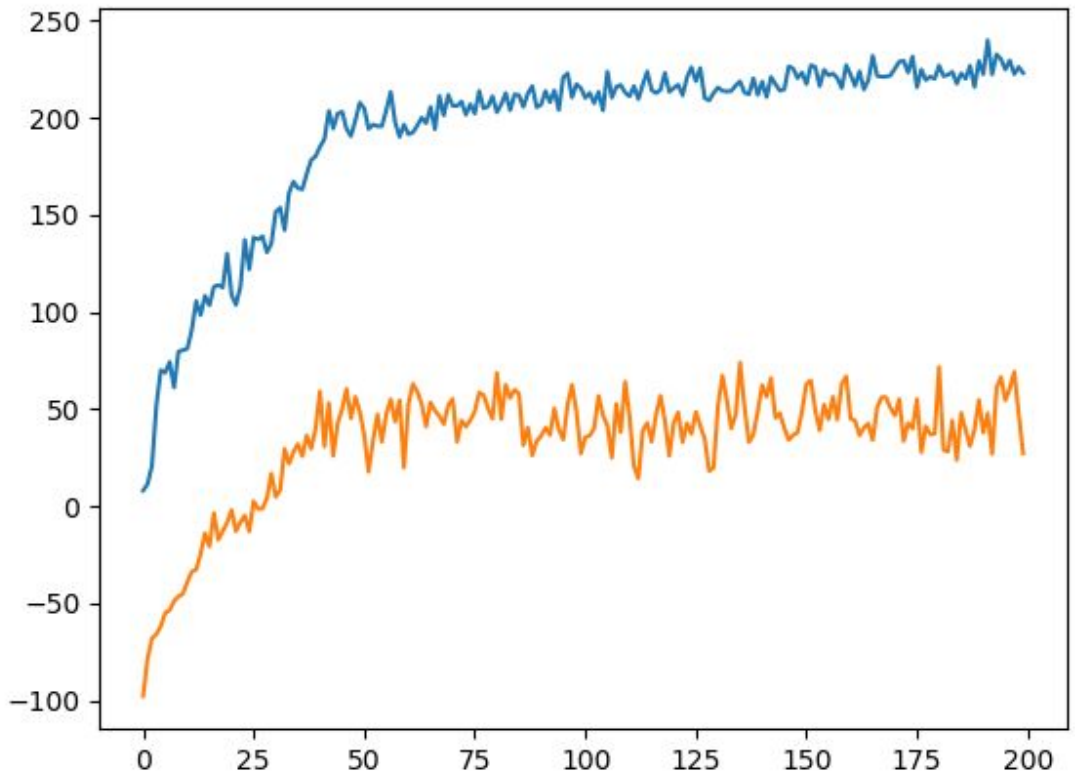
cross: 0.98
mutation: 0.02
select: 10
num_iter: 1000
gen_size: 100
num_generations: 100
num_repeat: 20



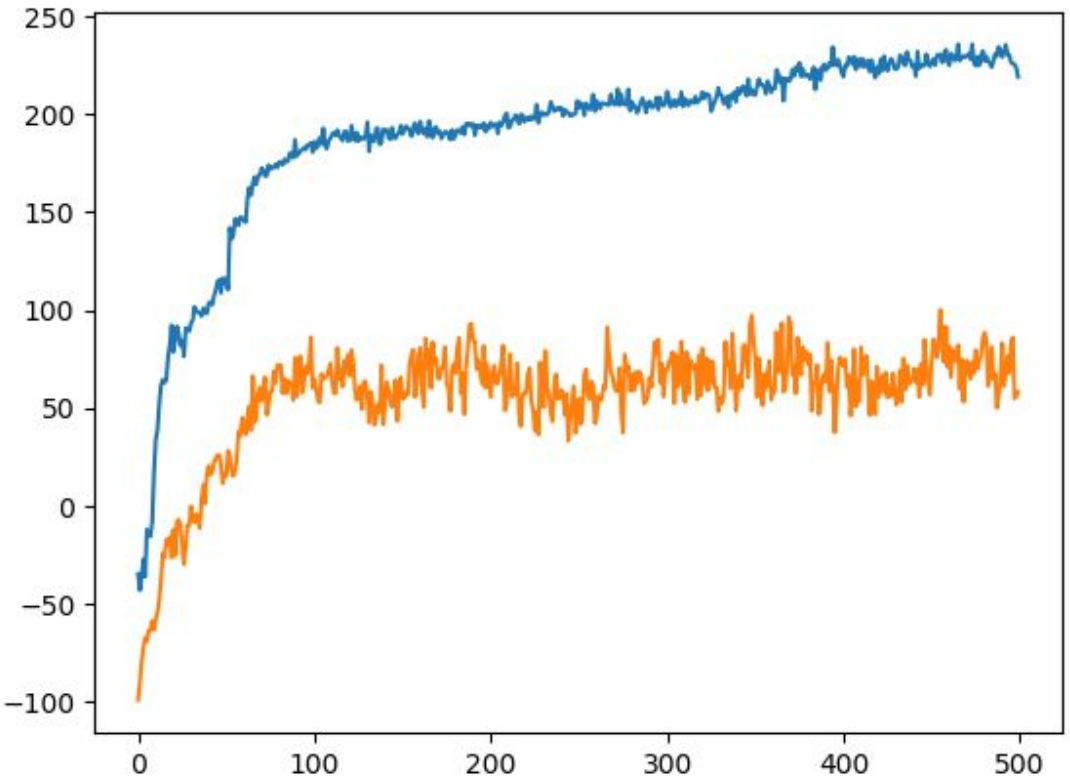
cross: 0.98
mutation: 0.02
select: 10
num_iter: 1000
gen_size: 100
num_generations: 100
num_repeat: 3



cross: 0.98
mutation: 0.02
select: 10
num_iter: 1000
gen_size: 100
num_generations: 200
num_repeat: 1
zeros_lidar



cross: 0.95
mutation: 0.02
select: 10
num_iter: 1000
gen_size: 100
num_generations: 500
num_repeat: 3
zeros_lidar



Observation

Type: Box(24)

Num	Observation	Min	Max	Mean
	hull_angle	0	2*pi	0.5
1	hull_angularVelocity	-inf	+inf	-
2	vel_x	-1	+1	-
3	vel_y	-1	+1	-
4	hip_joint_1_angle	-inf	+inf	-
5	hip_joint_1_speed	-inf	+inf	-
6	knee_joint_1_angle	-inf	+inf	-
7	knee_joint_1_speed	-inf	+inf	-
8	leg_1_ground_contact_flag	0	1	-
9	hip_joint_2_angle	-inf	+inf	-
10	hip_joint_2_speed	-inf	+inf	-
11	knee_joint_2_angle	-inf	+inf	-
12	knee_joint_2_speed	-inf	+inf	-
13	leg_2_ground_contact_flag	0	1	-
14-23	10 lidar readings	-inf	+inf	-

Actions

Type: Box(4) - Torque control(default) / Velocity control - Change inside /envs/box2d/bipedal_walker.py line 363

Num	Name	Min	Max
	Hip_1 (Torque / Velocity)	-1	+1

1	Knee_1 (Torque / Velocity)	-1	+1
2	Hip_2 (Torque / Velocity)	-1	+1
3	Knee_2 (Torque / Velocity)	-1	+1