

Errata

Model-Based Reinforcement Learning with Continuous States and Actions

(Deisenroth, Rasmussen, Peters, ESANN 2008)

April 15, 2008

1 Errata

- page 2: For the example system (underpowered pendulum) we used the immediate loss

$$g(\mathbf{x}_k, u_k) = 1 - \exp(-\mathbf{x}_k^T \text{diag}([1, 0.2])\mathbf{x}_k - 0.1u_k^2)$$

instead of $\mathbf{x}_k^T \text{diag}([1, 0.2])\mathbf{x}_k + 0.1u_k^2$ as claimed in the paper.

- page 5: The differences between the cumulative loss of the GP controller and the DP controller is 3.1%, not 1.66%.
- page 6: Figure 2 (page 6) in the paper should be replaced by the following one.

