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

\[ g(x_k, u_k) = 1 - \exp(-x_k^T \text{diag}(\begin{bmatrix} 1 & 0.2 \end{bmatrix})x_k - 0.1u_k^2) \]

instead of \( x_k^T \text{diag}(\begin{bmatrix} 1 & 0.2 \end{bmatrix})x_k + 0.1u_k^2 \) 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.