

Problem 1. (Reinforcement learning) .../3 points

You want to use reinforcement learning to control a drone. You model the drone as a Markov decision process

- Each of the drone's 4 motors are controlled by a voltage $V \in [0, 12]$. What is the action space of the Markov decision problem? **(1 point)**

$A = \dots\dots\dots$

- Let's $s \in \mathbb{R}^{12}$ denote the state of the drone, and consider a linear policy $\pi : \mathbb{R}^{12} \rightarrow A$ such that $\pi(s) = Ks$, where K is a matrix. Write down the dimensions of K . **(1 point)**

$K \in \dots\dots\dots$

- Consider the following trajectories where $s_t^i \in \mathbb{R}^{12}$ and $a_t^i \in A$, for $i \in \{1, 2, 3\}$:

trajectory 1	s_0	a_0^0	s_1^0	a_1^0	s_2^0	a_2^0	s_3^0	a_3^0	s_T^0
trajectory 2	s_0	a_0^1	s_1^1	a_1^1	s_2^1	a_2^1	s_3^1	a_3^1	s_T^1
trajectory 3	s_0	a_0^2	s_1^2	a_1^2	s_2^2	a_2^2	s_3^2	a_3^2	s_T^2

You want to train your agent to minimize the function $J(s_0, \pi) = \frac{1}{2}(s_T - s_G)^2$ where s_G is a goal state and T is a target time. Write down the empirical estimate of $J(s_0, \pi)$ based on the 3 trajectories above: **(1 point)**

$J(s_0, \pi) \approx \dots\dots\dots$

Problem 2. (Convolutional Neural Network)/1.5 points

Fill in the empty blocks in the convolution of X with a 2×2 filter w and a bias $b = 2$. **(1.5 points)**

0	1	1
0	1	0
1	1	1

X

1	0
0	1

w
Bias: $b = 2$

3	

$w * X$

