

An Imitation Learning Approach for the Control of a Low-Cost Low-Accuracy Robotic Arm for Unstructured Environments – Supplemental Material

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I. CDL WITHOUT NOISE

In the following, both the error norm (Fig. 1) and the component-wise trajectory (Fig. 2) for all tests performed with the Cartesian Deep Learning controller without additional noise are provided.

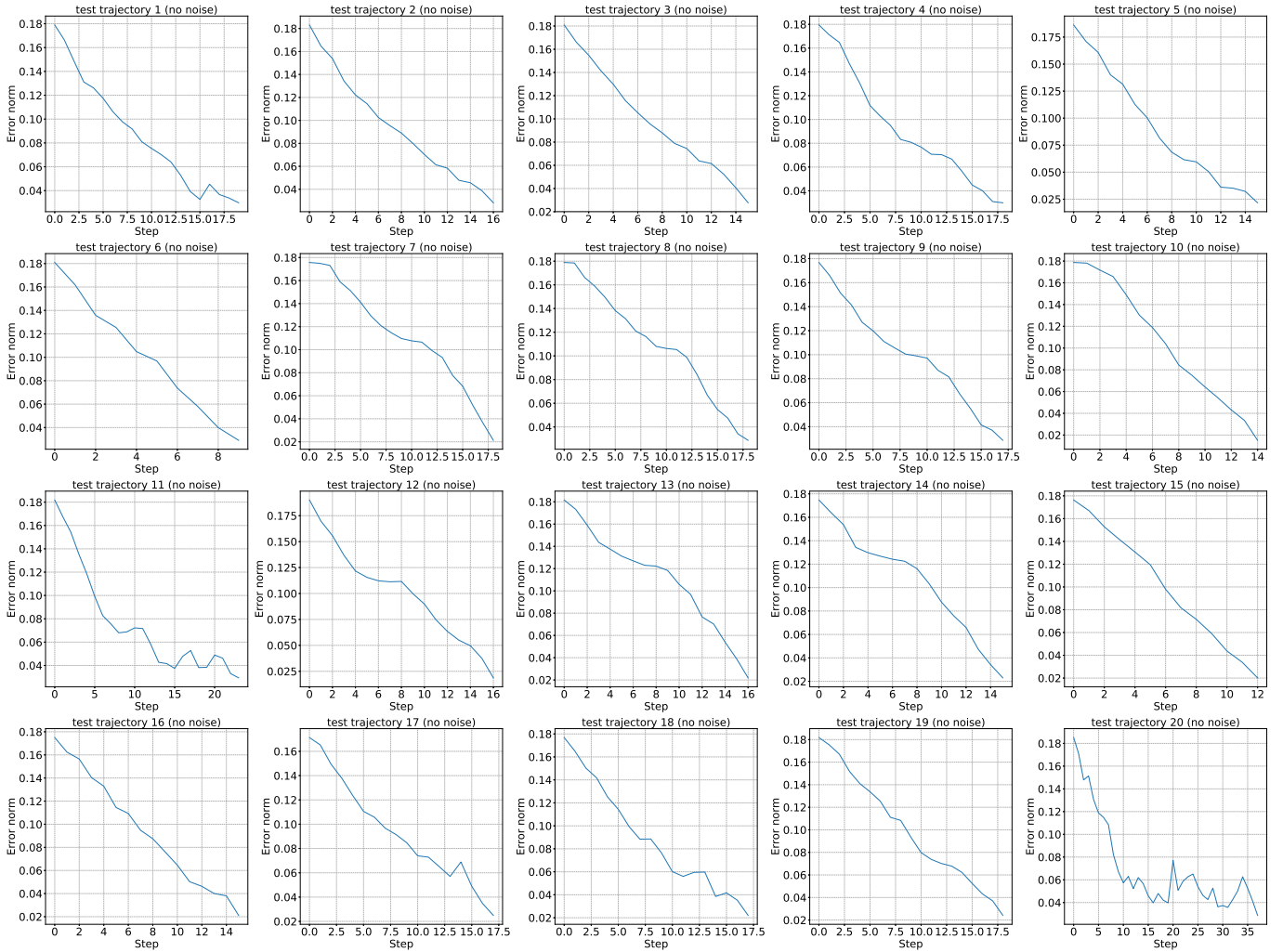


Fig. 1: CDL no noise error.

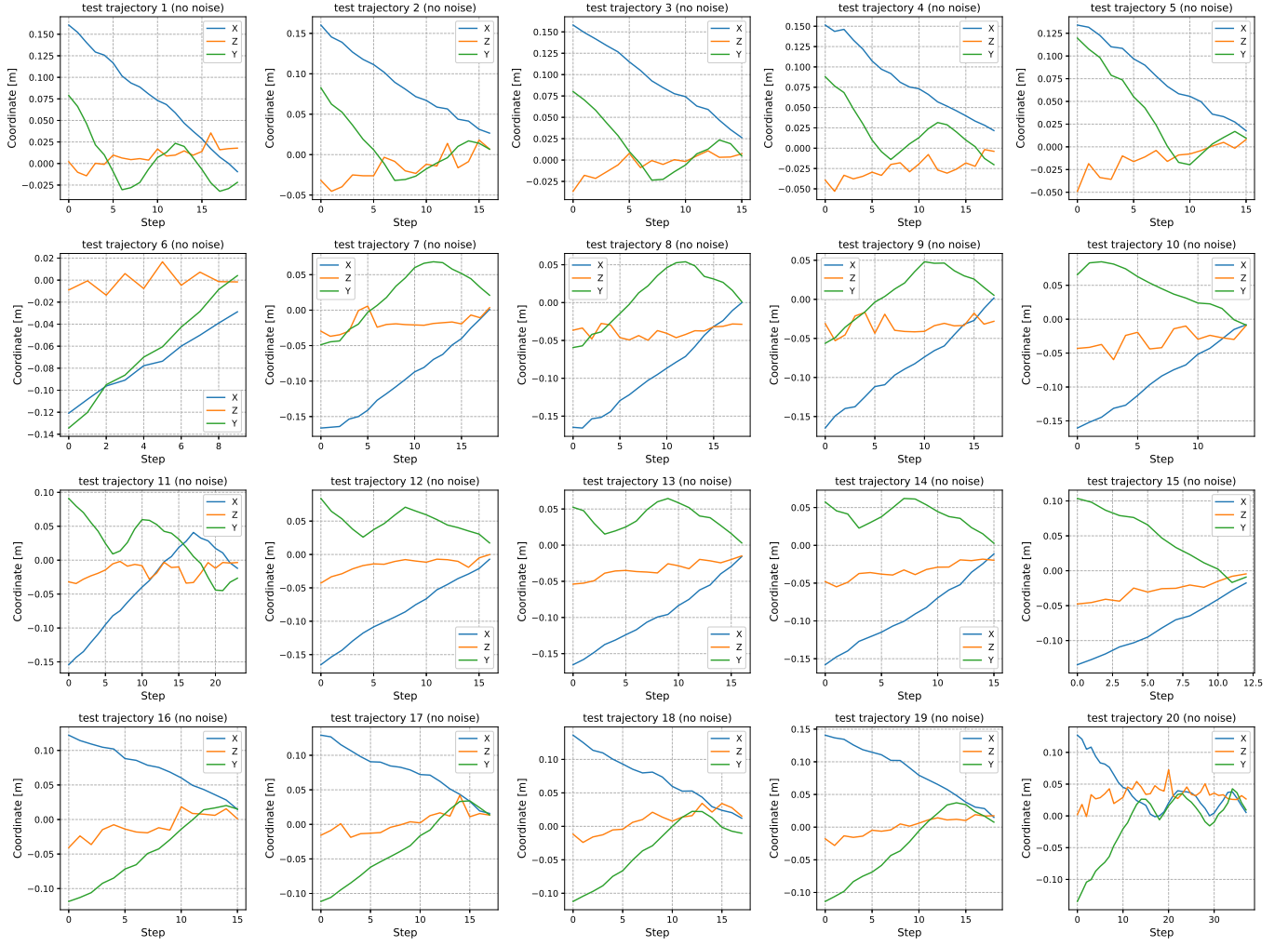


Fig. 2: CDL no noise trajectories.

II. CDL WITH NOISE

In the following, both the error norm (Fig. 3) and the component-wise trajectory (Fig. 4) for all tests performed with the Cartesian Deep Learning controller with additional noise are provided.

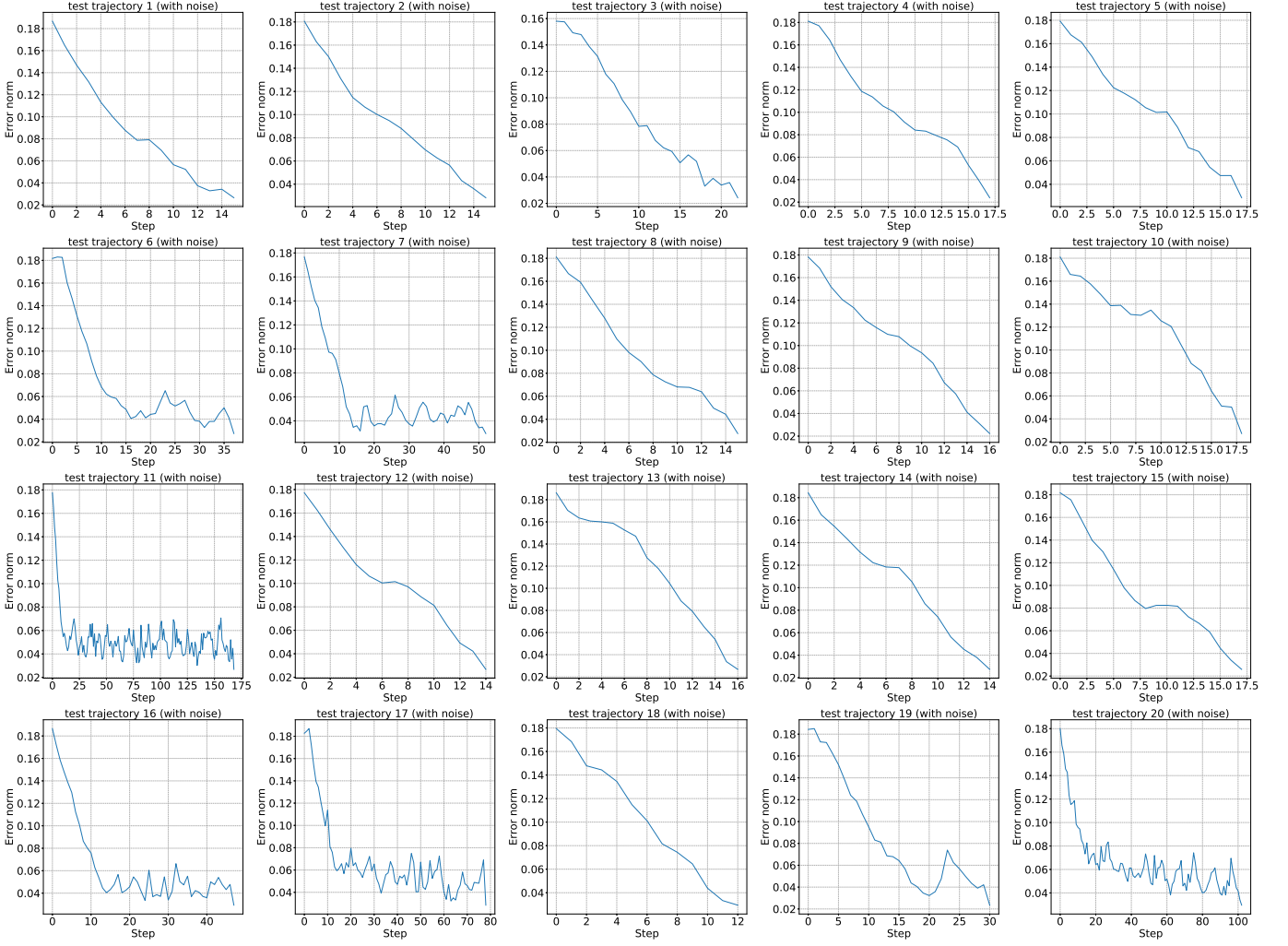


Fig. 3: CDL with noise error.

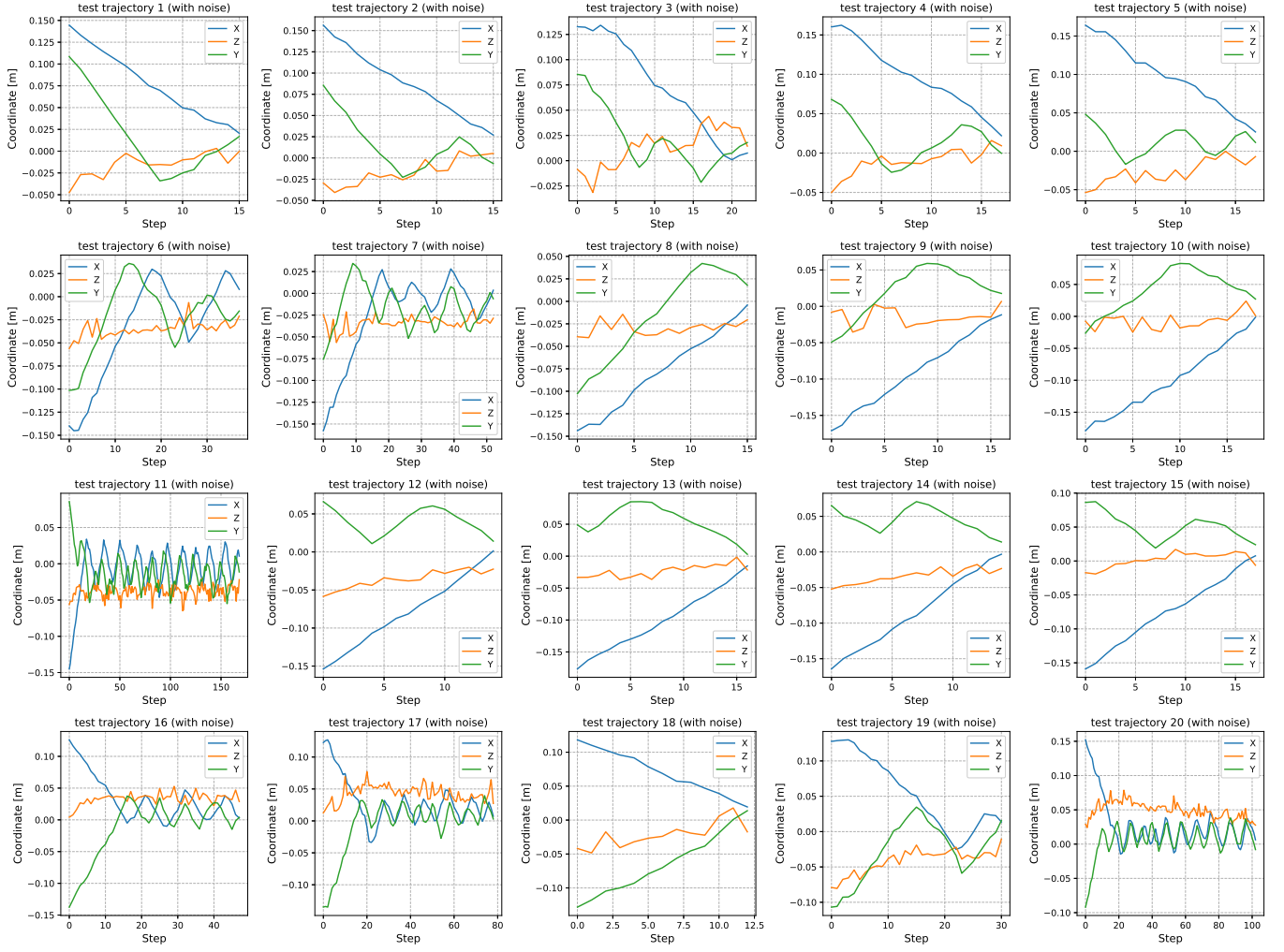


Fig. 4: CDL with noise trajectories.

III. MDL WITHOUT NOISE

In the following, both the error norm (Fig. 5) and the component-wise trajectory (Fig. 6) for all tests performed with the Motor Deep Learning controller without additional noise are provided.

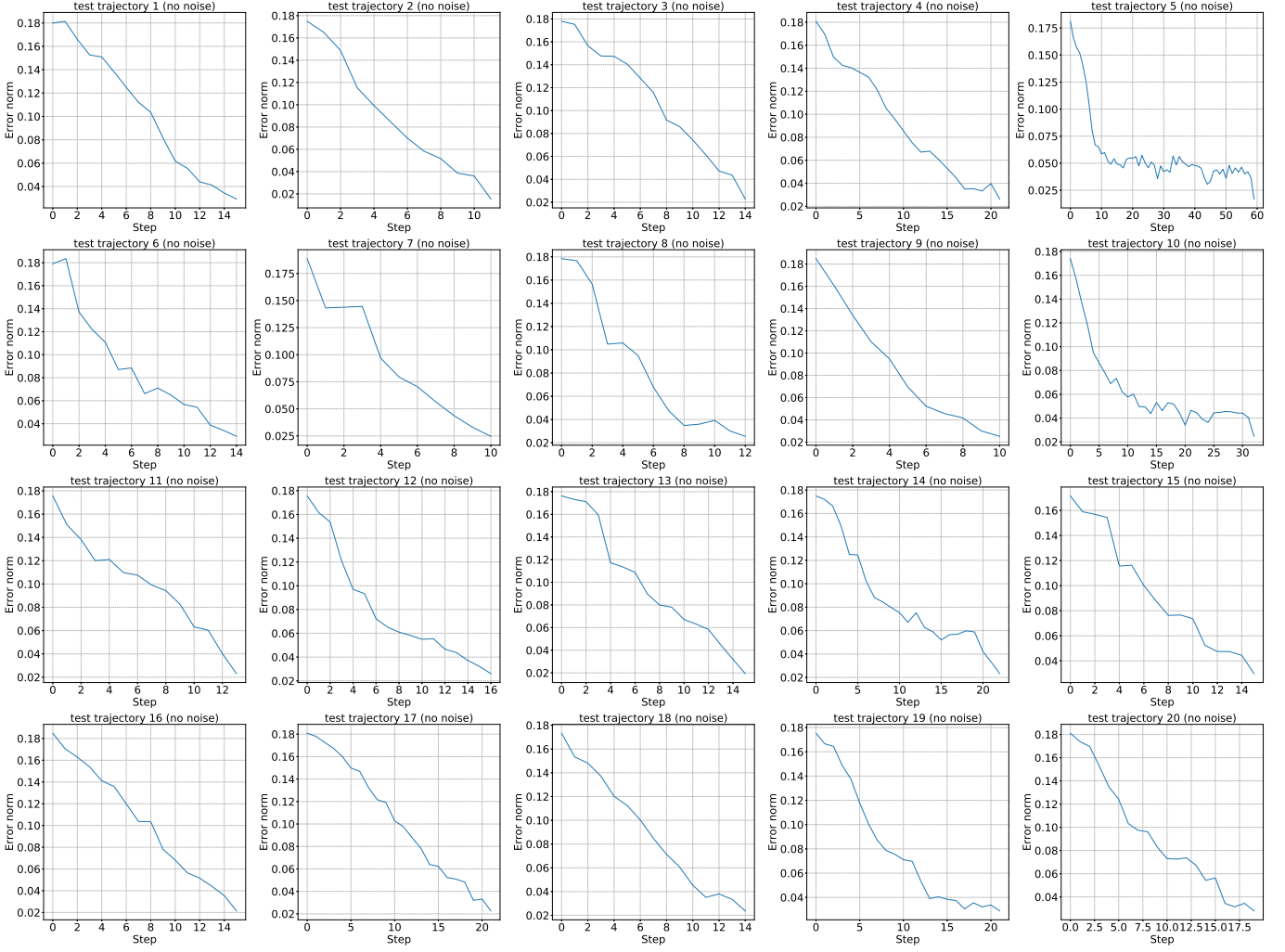


Fig. 5: MDL no noise error.

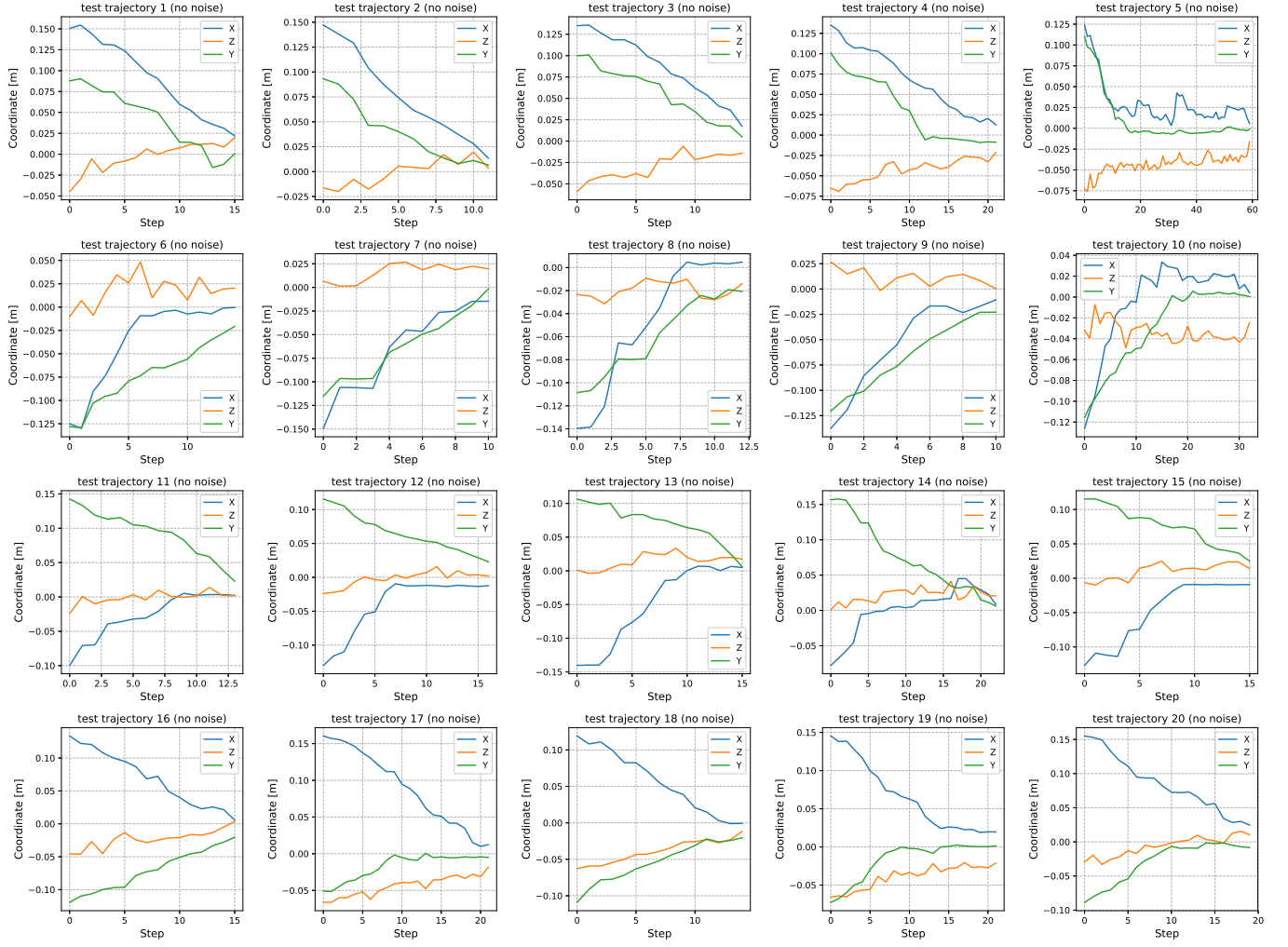


Fig. 6: MDL no noise trajectories.

IV. MDL WITH NOISE

In the following, both the error norm (Fig. 7) and the component-wise trajectory (Fig. 8) for all tests performed with the Motor Deep Learning controller with additional noise are provided.

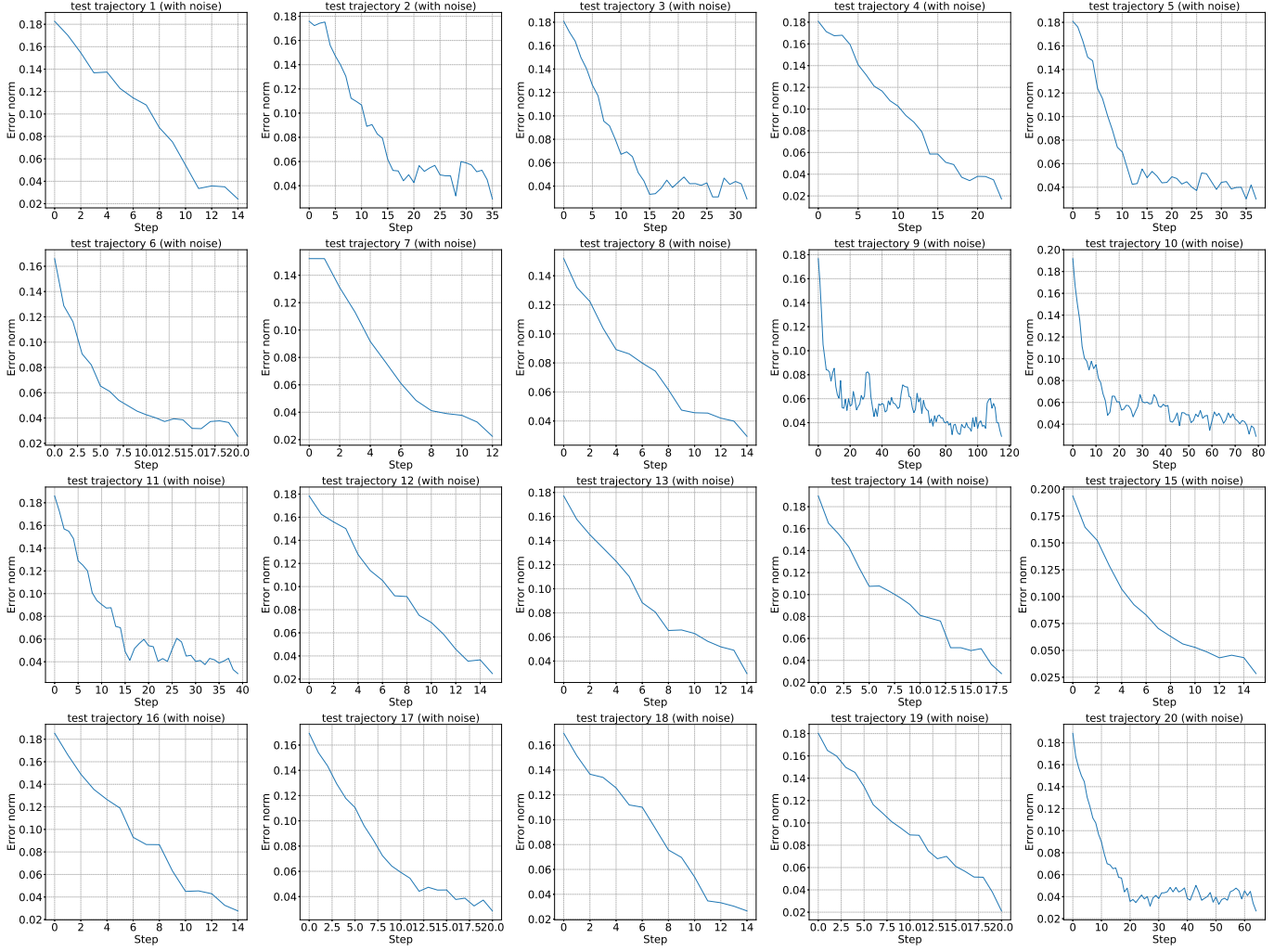


Fig. 7: MDL with noise error.

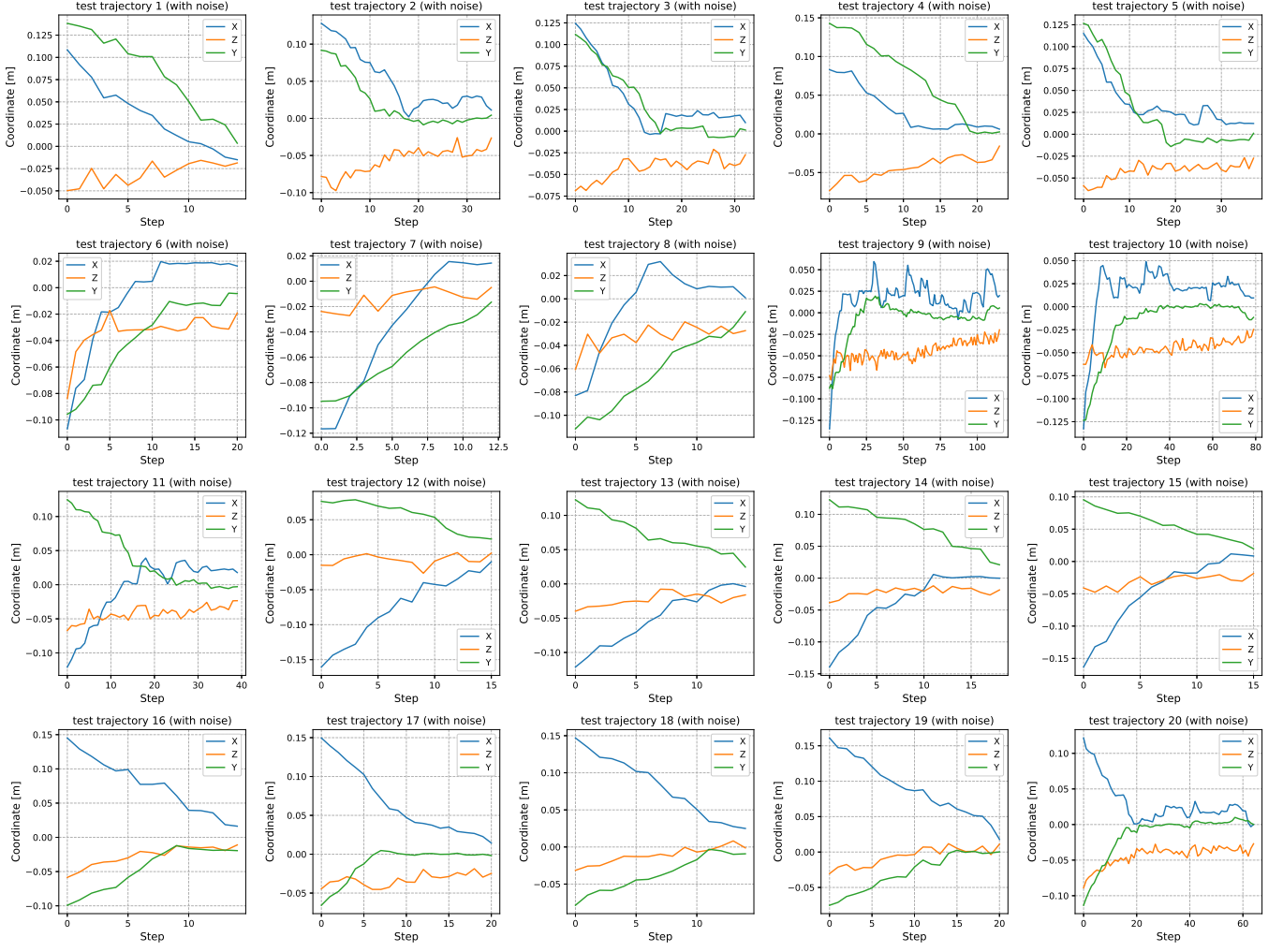


Fig. 8: MDL with noise trajectories.