

LIST OF FIGURES

2.1 Autonomous Navigation System	7
2.2 Types of machine learning	8
2.3 Diagram Interaksi antara Learner dan Environment	9
3.1 Behavior Based Kontrol pada Autonomous Trash Collector Robot	12
3.2 ROS Navigation stack block	14
3.3 Sub-space state of variables x_1 and x_2	16
3.4 Sub-space state of variables x_3 and x_4	17
3.5 Tampilan layar saat proses pelatihan (Gazebo simulator	21
3.6 grafik rqt proses pelatihan agen	21
3.7 Flow diagram of the learning process by the Q - learning algorithm	23
4.1 Parameters of epoch search strategies	24
4.2 Accumulated agent reward through epochs for different search strategies . .	25
4.3 The average number of agent steps through epochs for different search strategies	25
4.4 Average number of agent steps through epochs for a parameter	26
4.5 Accumulated agent reward through epochs for a parameter	27
4.6 Accumulated agent reward through epochs for a parameter	28
4.7 Average number of agent steps through epochs for a parameter	28
4.8 Average number of agent steps through epochs, final training	29
4.9 Accumulated agent reward through epochs, final training	30
4.10 Q-table at the end of the training algorithm	30
4.11 algorithm testing in simulation environment, experiment 1	31
4.12 algorithm testing in simulation environment, experiment 2	32
4.13 rqt graph of the hybrid algorithm testing process in a simulation environment	32