

## A Imitation learning experiment losses

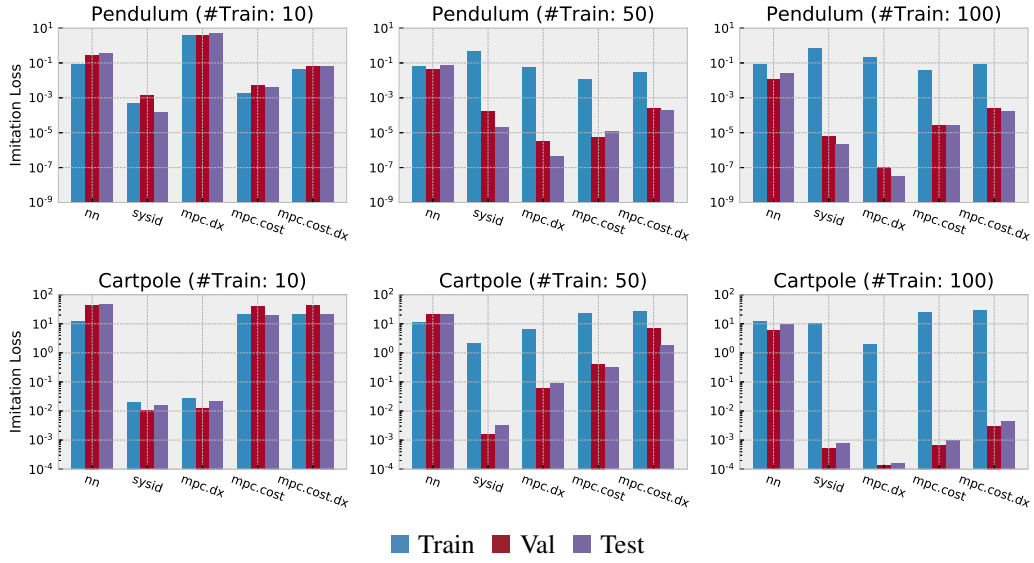


Figure 6: Learning results on the (simple) pendulum and cartpole environments. We select the best validation loss observed during the training run and report the corresponding train and test loss. Every datapoint is averaged over four trials.