TRUE FALSE

1. Are there situations in which a robot should not try to maximize its reward?   ☐   ☐

2. Why are the utility functions formulated in differential form (i.e. using a time derivative) in the utility function method?

1. Yes. An example is given in the lecture notes, pp. 110-111.

2. The differential form of the utility functions leads to a noise-tolerant decision-making.