CS234 Winter 2020
MuJoCo License and Installation Guide

February 10, 2020

(This is only for students enrolled in CS234 in Winter 2019-20)

MuJoCo stands for Multi-Joint dynamics with Contact that will be used in assignment 3 and also many RL papers use it as a benchmark.

We have provided MuJoCo license for enrolled students in CS234. You can also use the license for your projects. Please Do not share this license with anyone outside the class. This is part of our user agreement, that only enrolled students, CAs and the instructor can use the license.

MuJoCo Installation Guide

Prerequisites: Python3.6 and
Tensorflow1.7.1

Windows users: We recommend you do this assignment on a Linux VM. You can use your Azure instance from assignment 2.

1. Download mujoco131 for your OS from here. Be sure to download version 131. **Make sure to download and install the right Mujoco version for your Operating System. (Mac users please use mjpro131_osx, Windows users should use either mjpro131_win64 or mjpro131_win32 depending upon if your system is 64 bit or 32 bit version respectively, Linux users install mjpro131_linux)**. VM users can scp this to their machine, or download directly using:

   ```
   wget https://www.roboti.us/download/mjpro131_linux.zip
   ```

2. Extract the downloaded package to `~/.mujoco/mjpro131`

   ```
   unzip mjpro131_*.zip -d ~/.mujoco
   ```

3. Download the license file and place it in `~/.mujoco/mjkey.txt` from here (Only enrolled students and CAs have access to this).

4. Run the command:
   ```
   sudo chmod -R 755 ~/.mujoco/mjpro131
   ```

5. Install the following dependencies:
   ```
   pip3 install gym==0.9.1
   pip3 install mujoco-py==0.5.7
   pip3 install scipy
   pip3 install matplotlib
   ```

6. VM users: Edit config.py to set self.record = False in the three environment config objects.

7. Verify that the following command doesn't throw a fatal exception (PkgResourcesDeprecationWarning is fine)

   ```
   python3 -c 'import gym;
   gym.make("InvertedPendulum-v1")'
   ```