Lecture 19: Learning 8

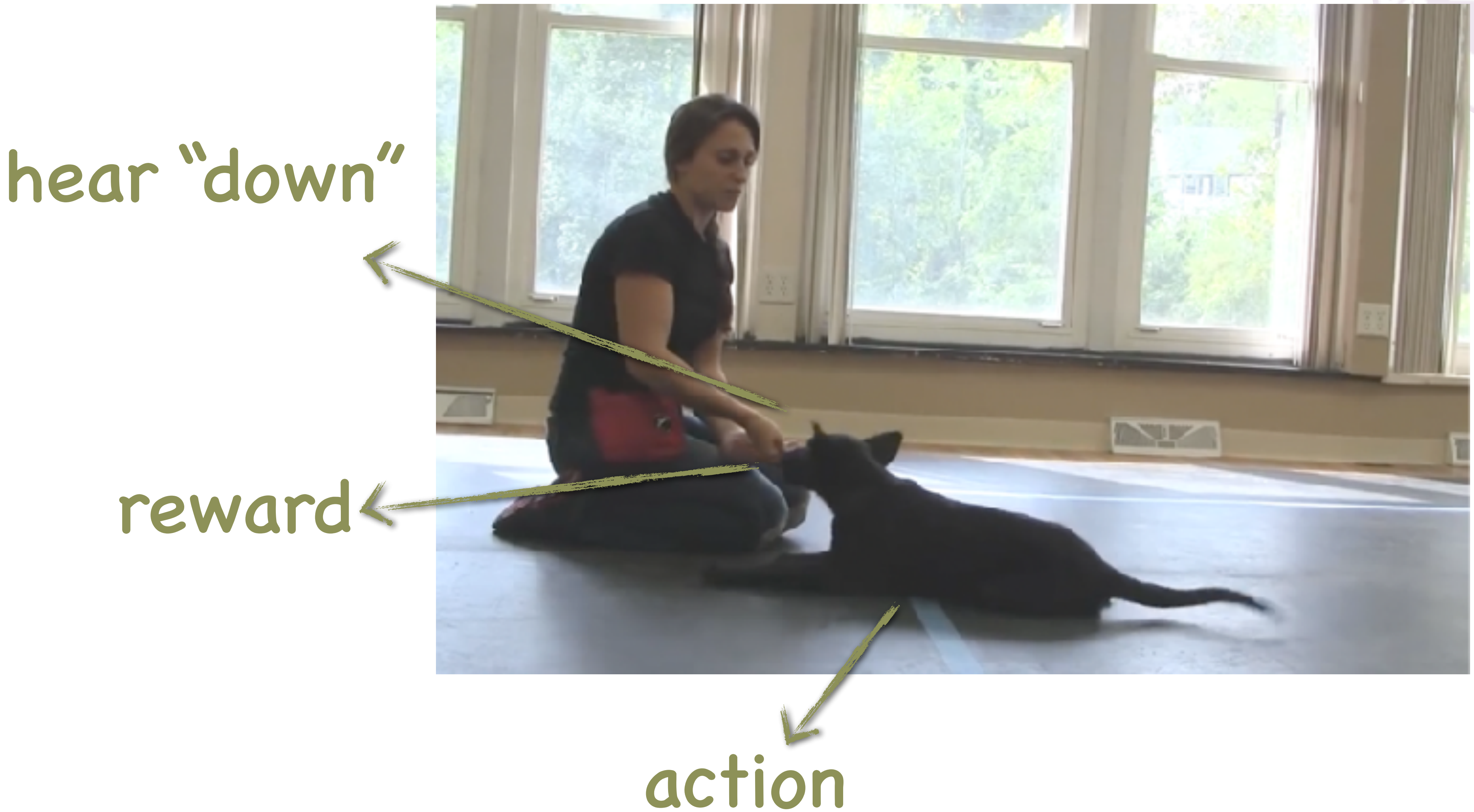
http://cs.nju.edu.cn/yuy/course_ai17.ashx

How to train a dog?

PHASE 1

DOWN

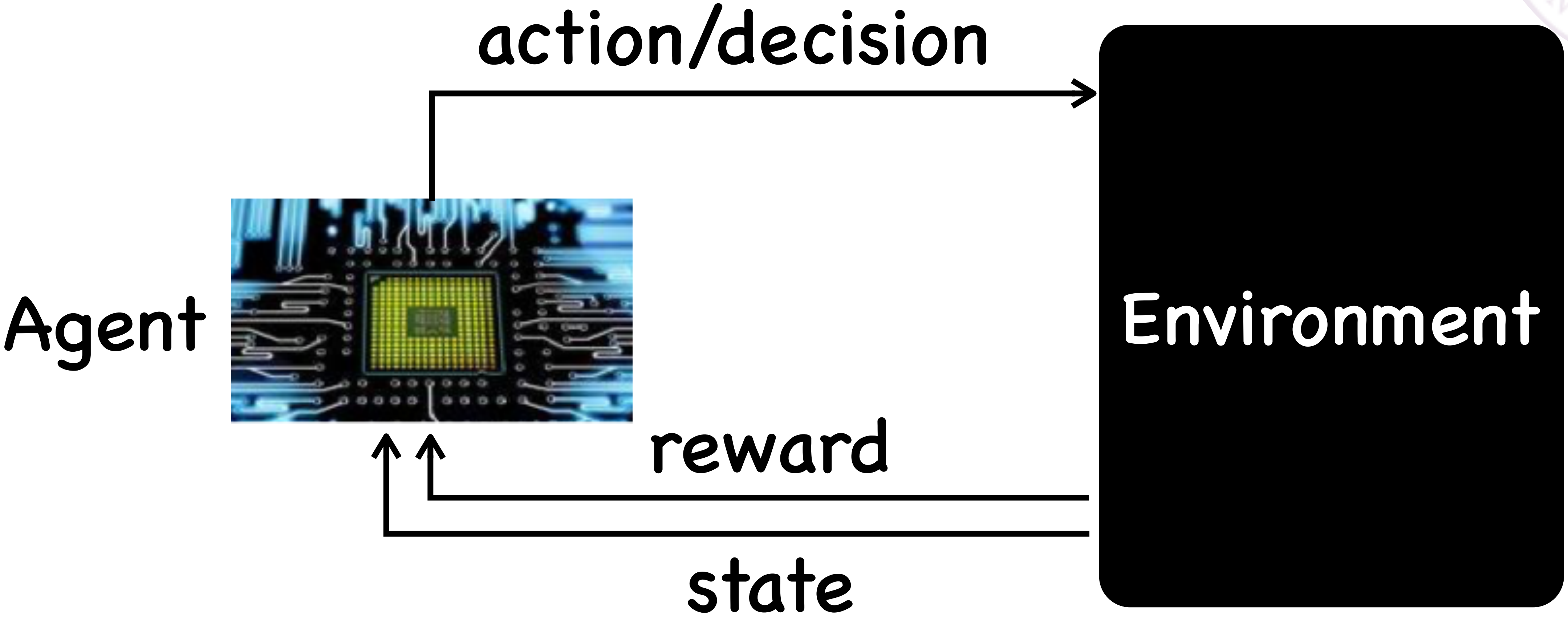
How to train a dog?



dog learns from rewards to adapt to the environment

can computers do similarly?

Reinforcement learning setting



$<A,\ S,\ R,\ P>$

Action space: A

State space: S

Reward: $R : S \times A \times S \to \mathbb{R}$

Transition: $P : S \times A \to S$

Reinforcement learning setting

$< A, \; S, \; R, \; P >$

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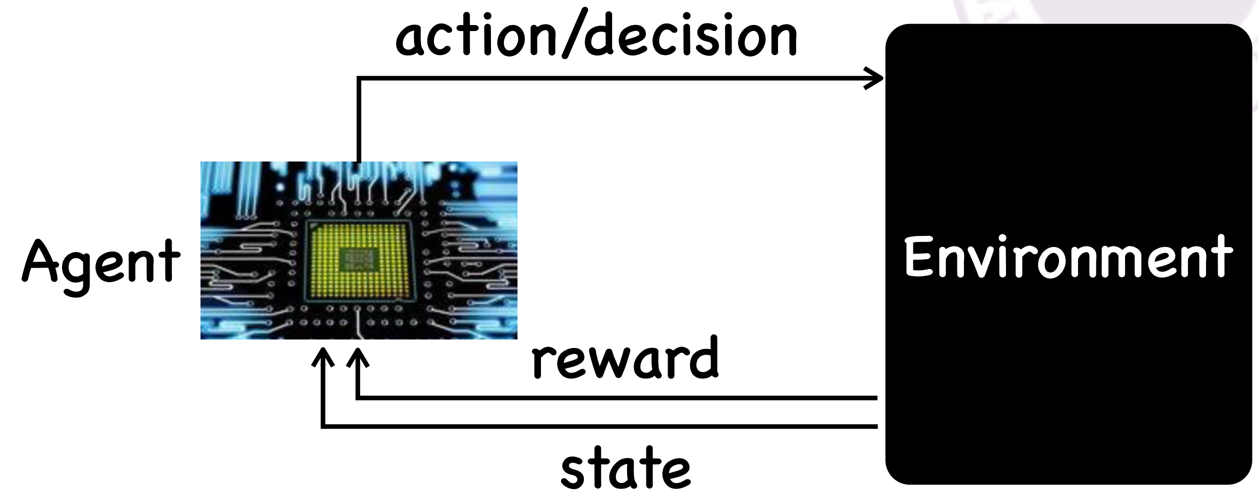

Agent:

Policy: $\pi : S \times A \to \mathbb{R}, \quad \sum_{a \in A} \pi(a|s) = 1$

Policy (deterministic): $\pi : S \to A$

Agent's view: $s_0, \; a_0, \; r_1, s_1, \; a_2, \; r_2, s_2, \; a_3, \; r_3, s_3, \ldots$

$\pi(s_0) \quad \pi(s_1) \quad \pi(s_2)$

Reinforcement learning setting

$<A,\ S,\ R,\ P>$

Action space: A

State space: S

Reward: $R : S \times A \times S \to \mathbb{R}$

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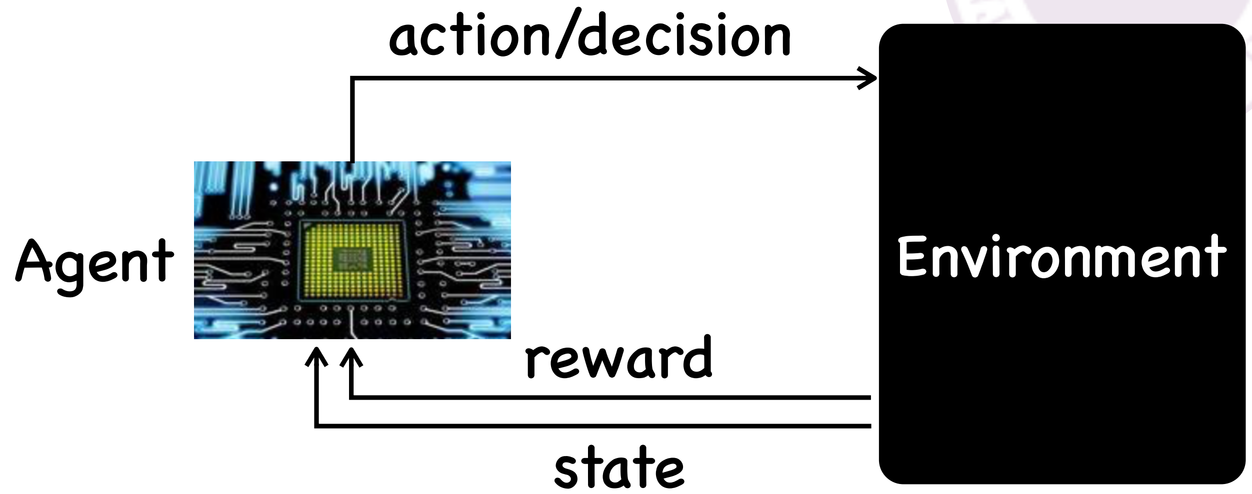


Agent: Policy: $\pi : S \times A \to \mathbb{R}, \quad \sum_{a \in A} \pi(a|s) = 1$

Policy (deterministic): $\pi : S \to A$

Agent's goal:

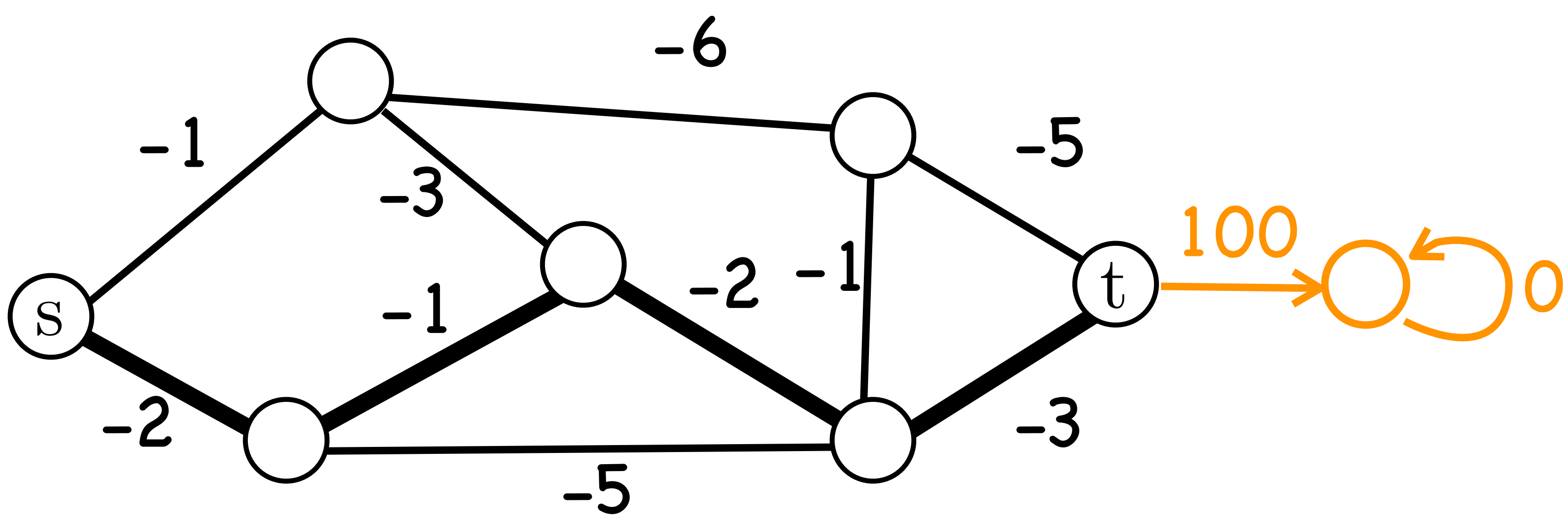
learn a policy to maximize long-term total reward

T-step: $\sum_{t=1}^{T} r_t$ discounted: $\sum_{t=1}^{\infty} \gamma^t r_t$

all RL tasks can be defined by maximizing total reward

Reward examples

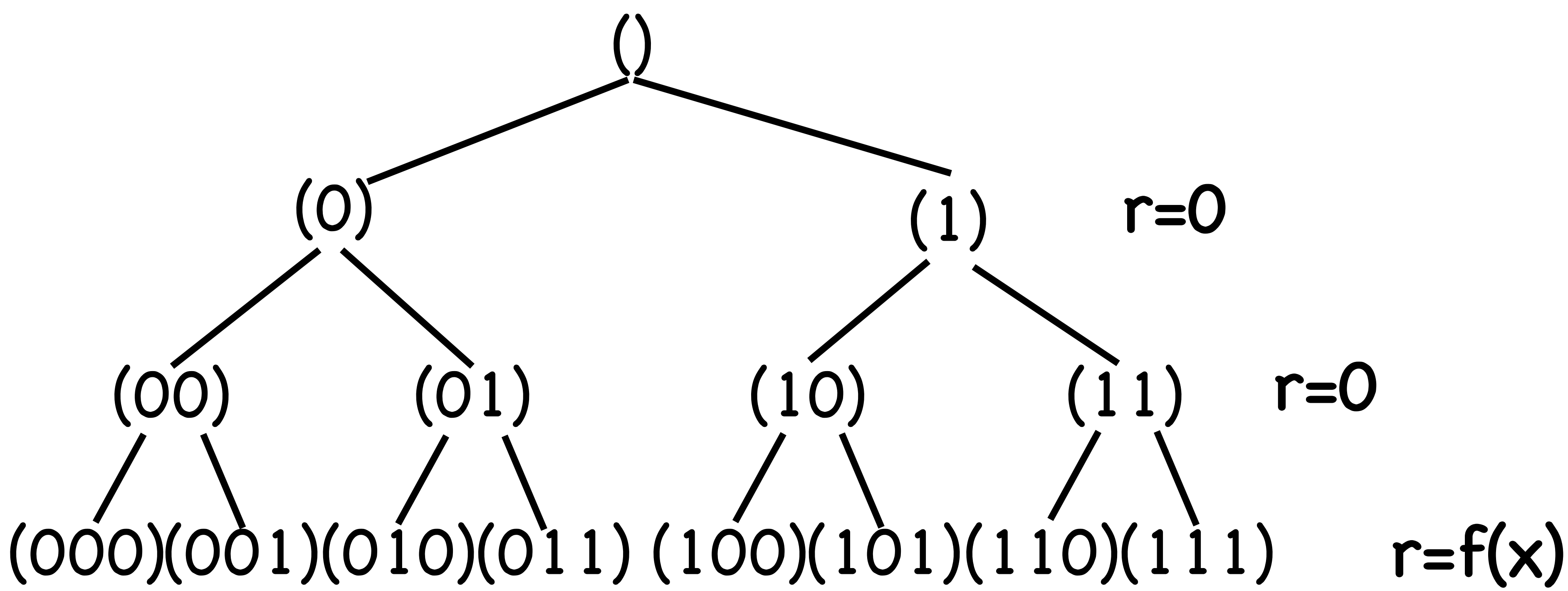
shortest path:



- every node is a state, an action is an edge out
- reward function = the negative edge weight
- optimal policy leads to the shortest path

Reward examples

general binary space problem $\max_{x \in \{0,1\}^n} f(x)$



solving the optimal policy is NP-hard!

Difference between RL and planning?

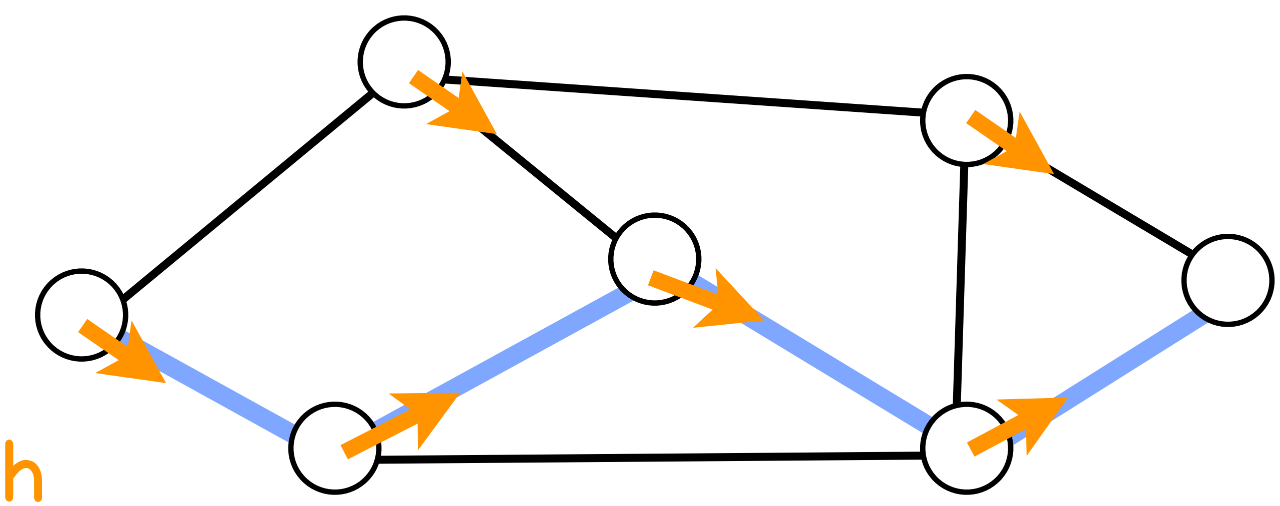
what if we use planning/search methods to find actions that maximize total reward

Planing: find an optimal solution

RL: find an optimal policy from samples

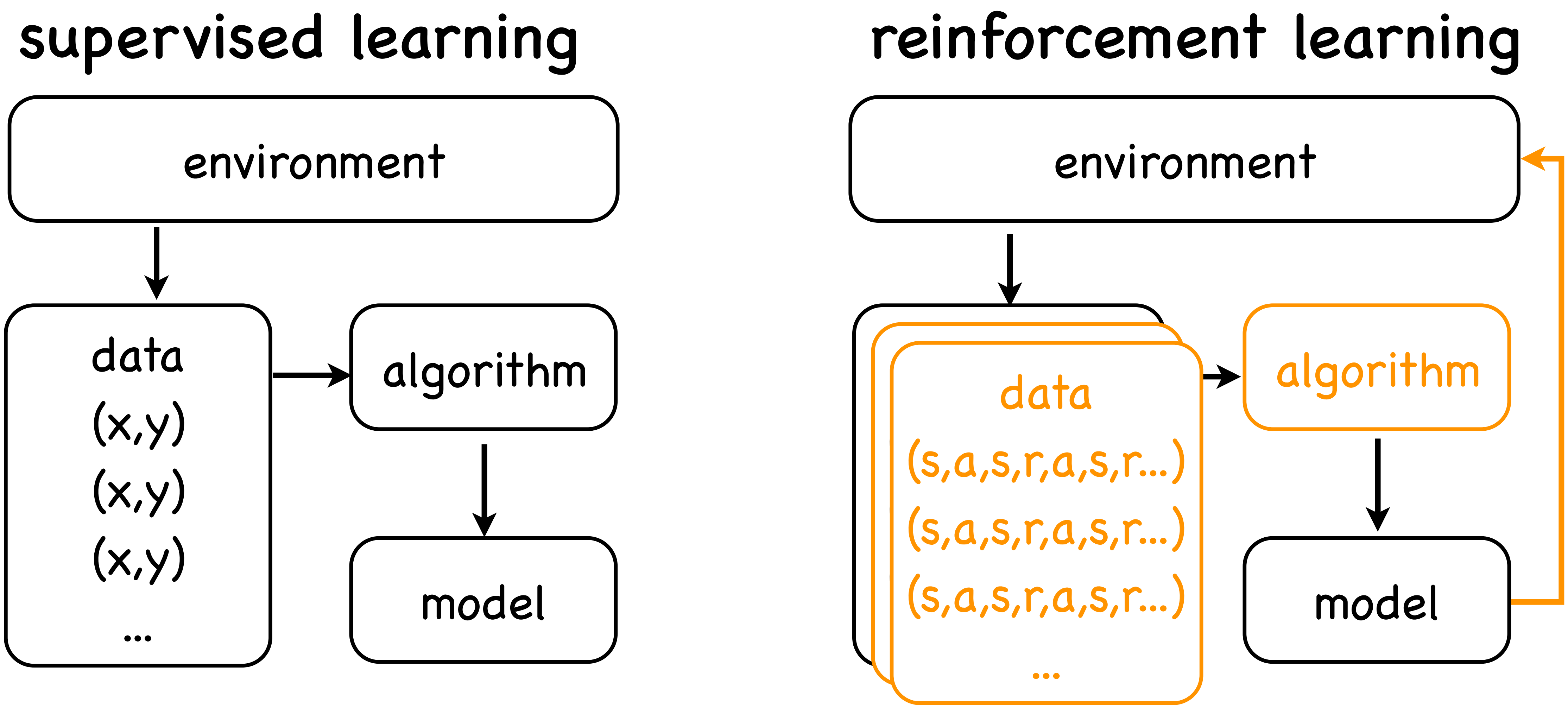
planning: shortest-path

RL: shortest-path policy without knowing the graph



Difference between RL and SL?

supervised learning also learns a model ...

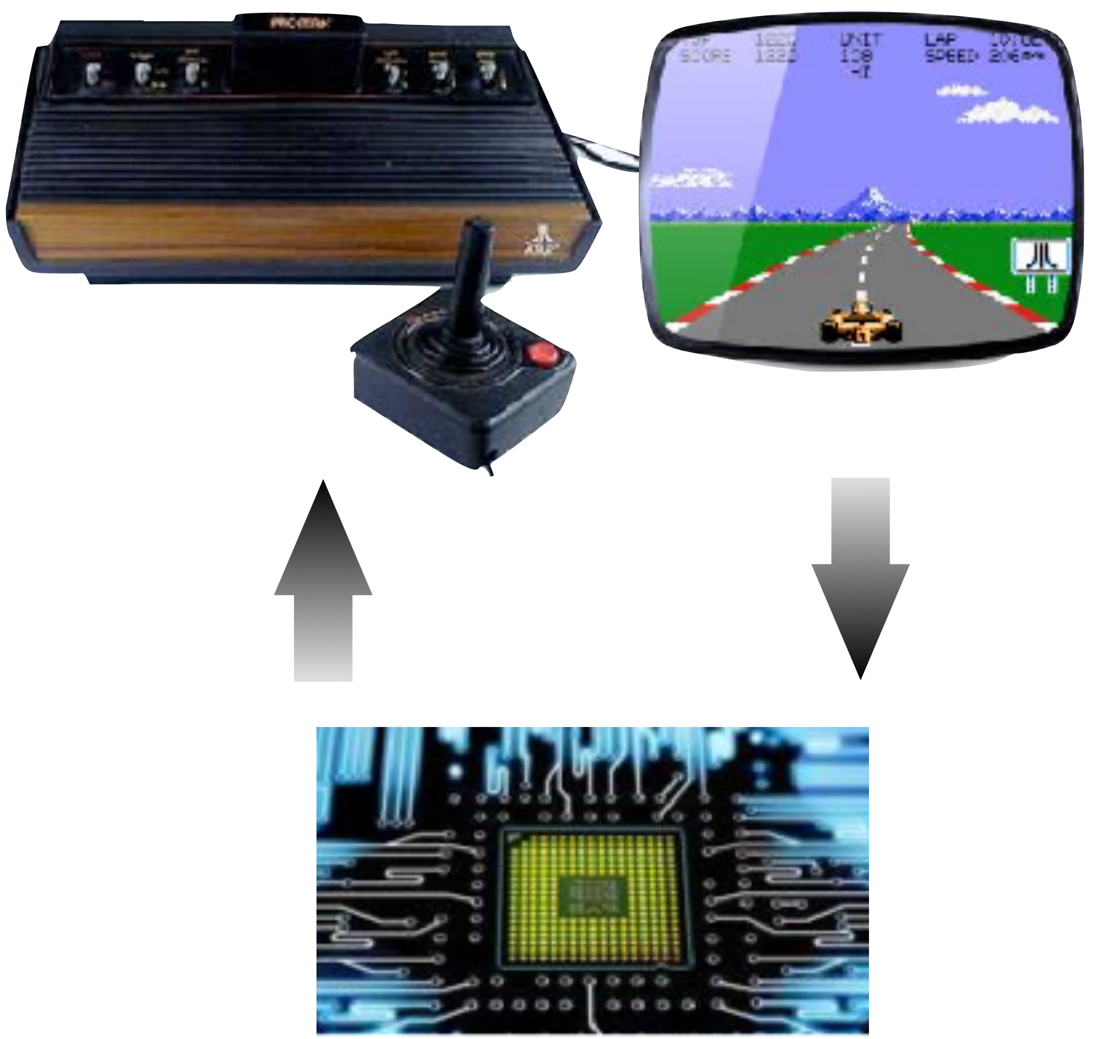


supervised learning	reinforcement learning
learning from labeled data	learning from delayed reward
open loop	closed loop
passive data	explore environment

Applications

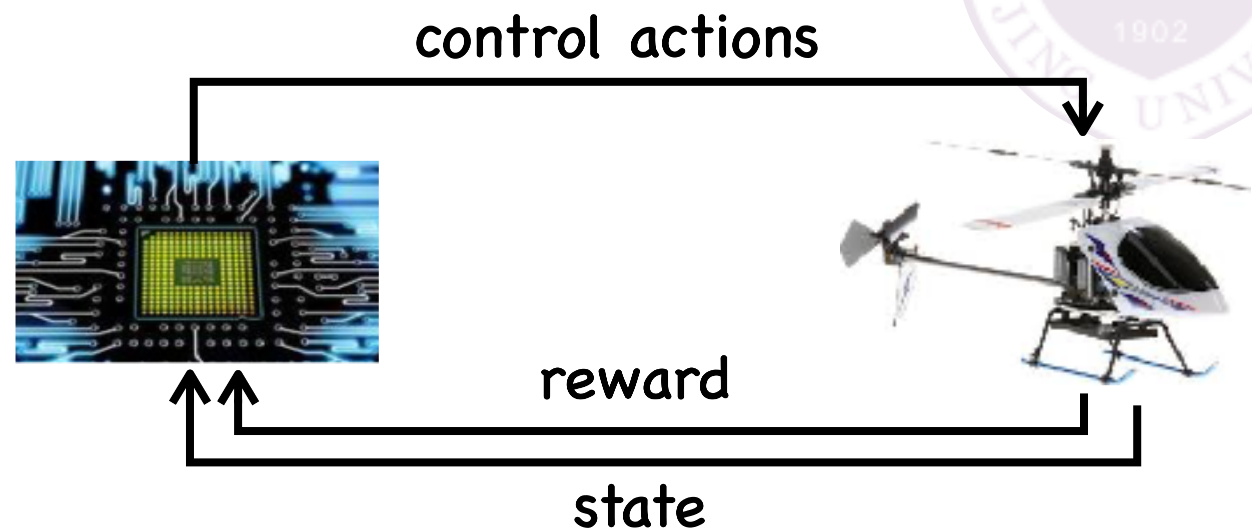
Deepmind Deep Q-learning on Atari

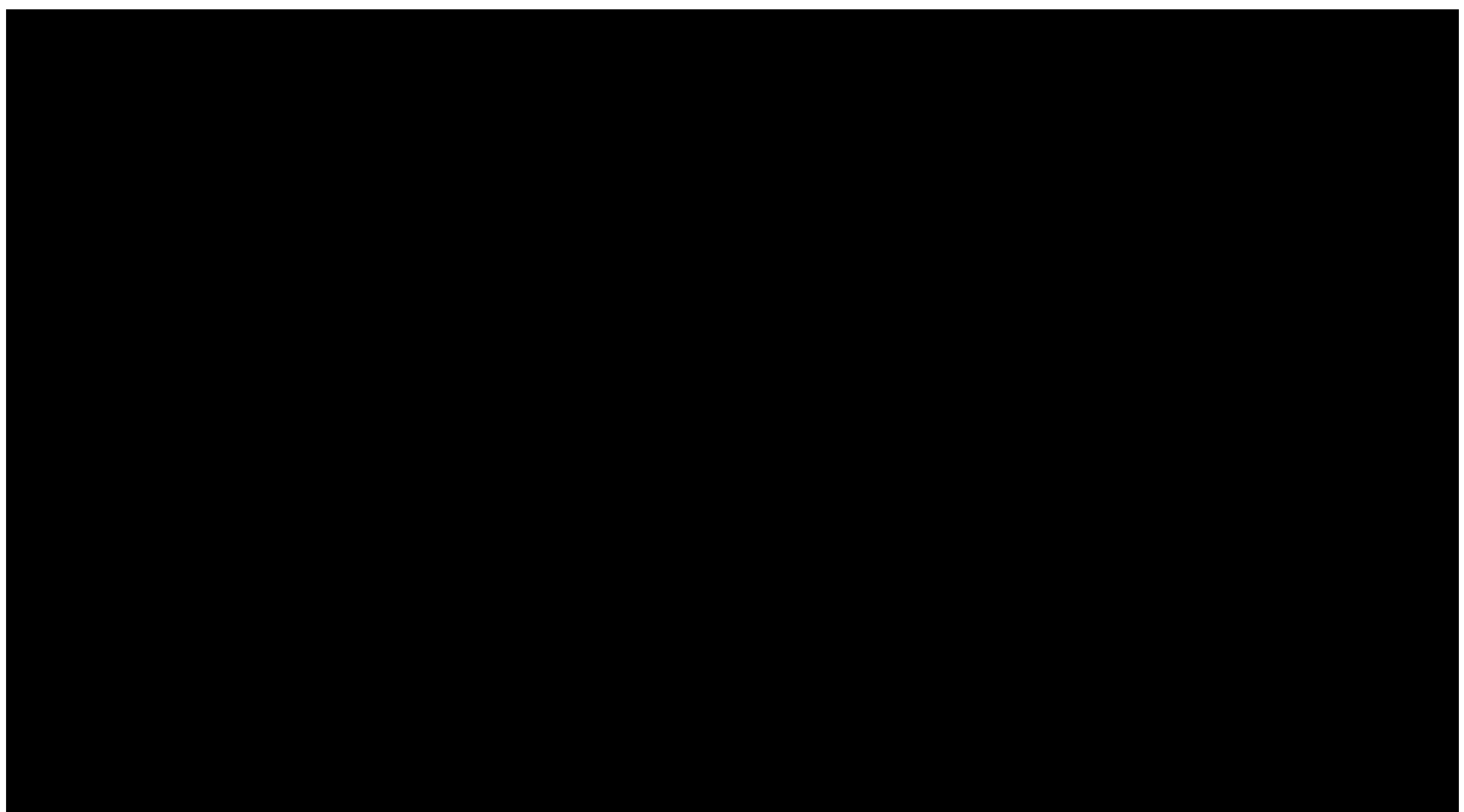
[Mnih *et al*. Human-level control through deep reinforcement learning. Nature, 518(7540): 529-533, 2015]



Applications

learning robot skills





https://www.youtube.com/watch?v=VCdxqn0fcnE

More applications

- Search
- Recommendation system
- Stock prediction
- …

every decision changes the world

Markov Decision Process

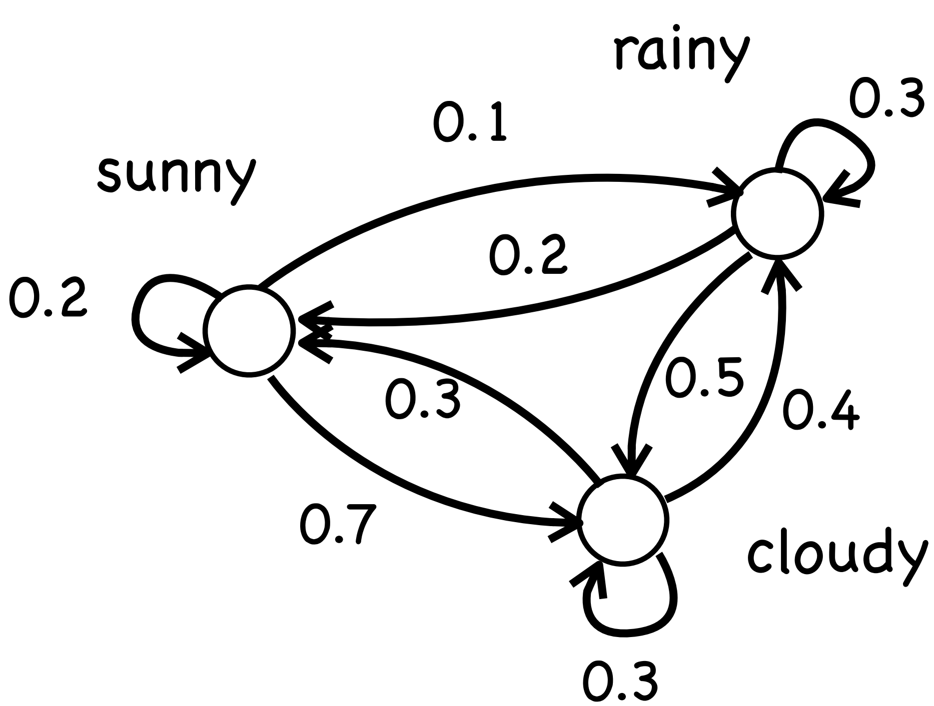
essential mathematical model for RL

Markov Process

(finite) state space S, transition matrix P

a process $s_0, s_1, \ldots$ is Markov if has no memory

$$P(s_{t+1} \mid s_t, \ldots, s_0) = P(s_{t+1} \mid s_t)$$ discrete S -> Markov chain



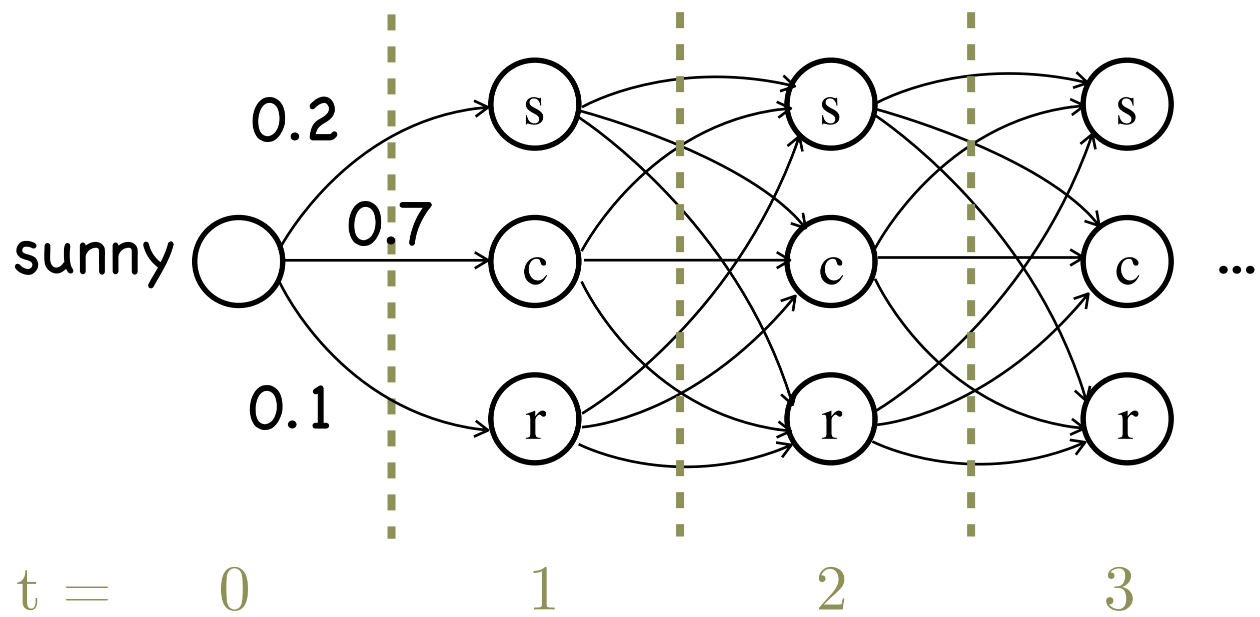
$P =$

	s	c	r
sunny	0.2	0.7	0.1
cloudy	0.3	0.3	0.4
rainy	0.2	0.5	0.3

$$\boldsymbol{s}_{t+1} = \boldsymbol{s}_t P = \boldsymbol{s}_0 P^{t+1}$$

Markov Process

horizontal view



stationary distribution: $s == sP$

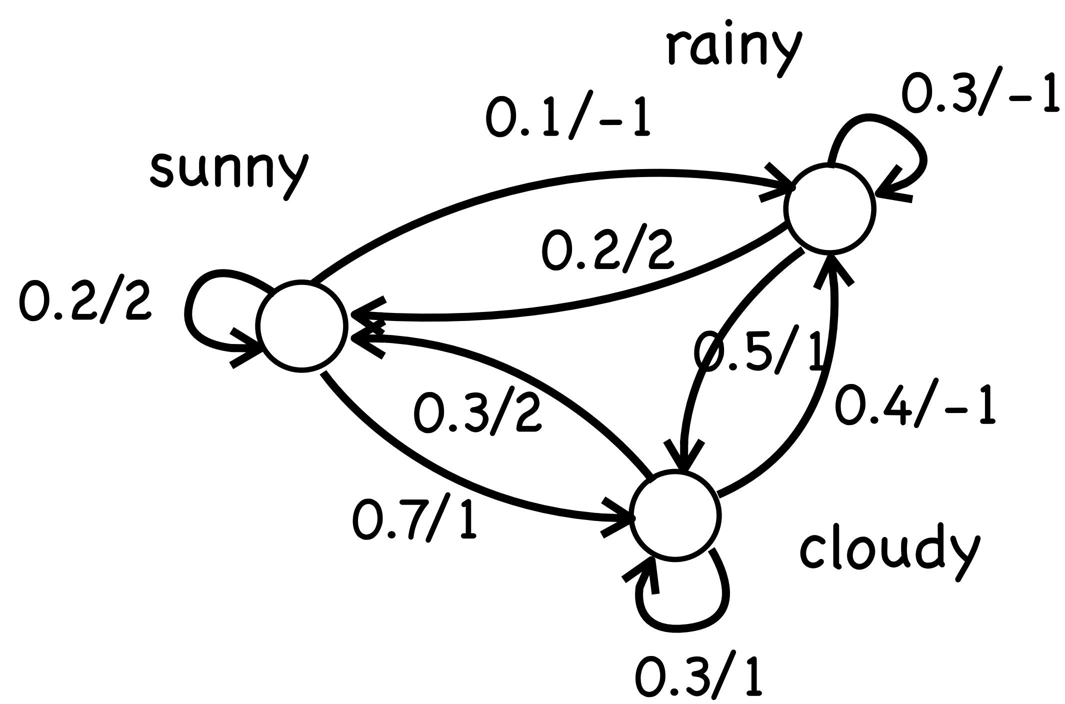
sampling from a Markov process:

s, c, c, r ...

s, c, s, c ...

Markov Reward Process

introduce reward function R



how to calculate the long-term total reward?

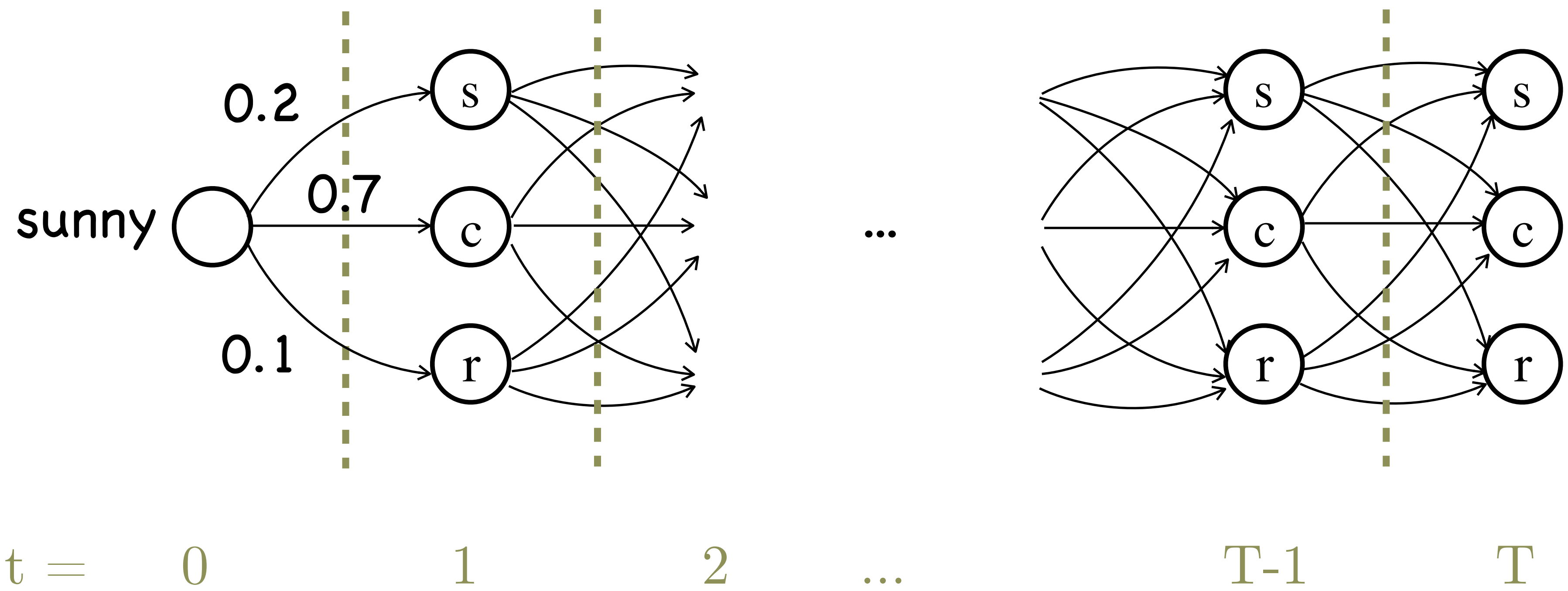
$$V(\text{sunny}) = E[\sum_{t=1}^{T} r_t | s_0 = \text{sunny}]$$

$$V(\text{sunny}) = E[\sum_{t=1}^{\infty} \gamma^t r_t | s_0 = \text{sunny}]$$

value function

Markov Reward Process

horizontal view: consider T steps

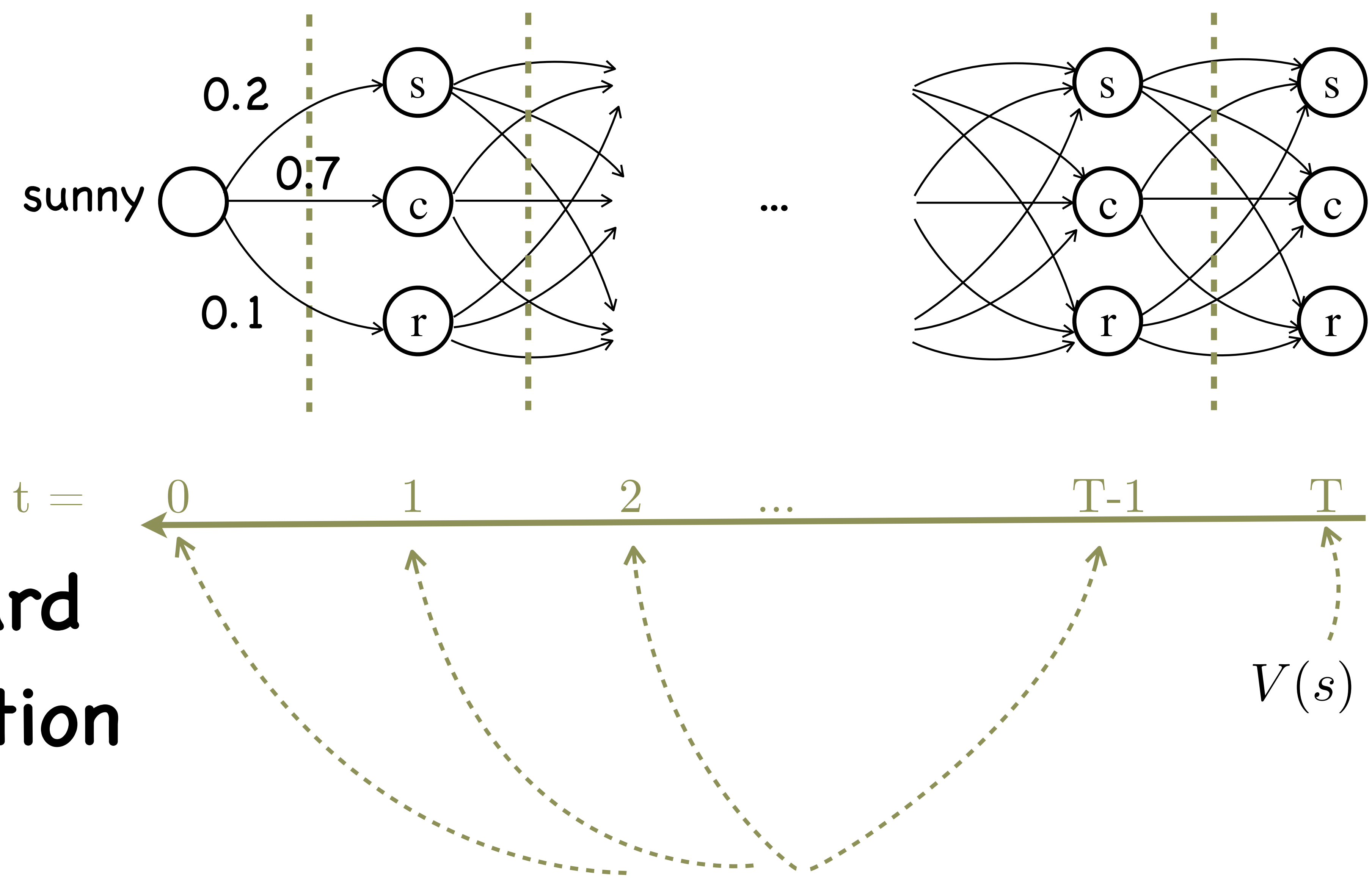


recursive definition:

$$
\begin{aligned}
V(\text{sunny}) =& P(\text{s}|\text{s})[R(\text{s}) + V(\text{s})] \\
&+ P(\text{c}|\text{s})[R(\text{c}) + V(\text{c})] \\
&+ P(\text{r}|\text{s})[R(\text{r}) + V(\text{r})]
\end{aligned}
\qquad = \sum_{s} P(s|\text{sunny})\big(R(s) + V(s)\big)
$$

Markov Reward Process

horizontal view: consider T steps



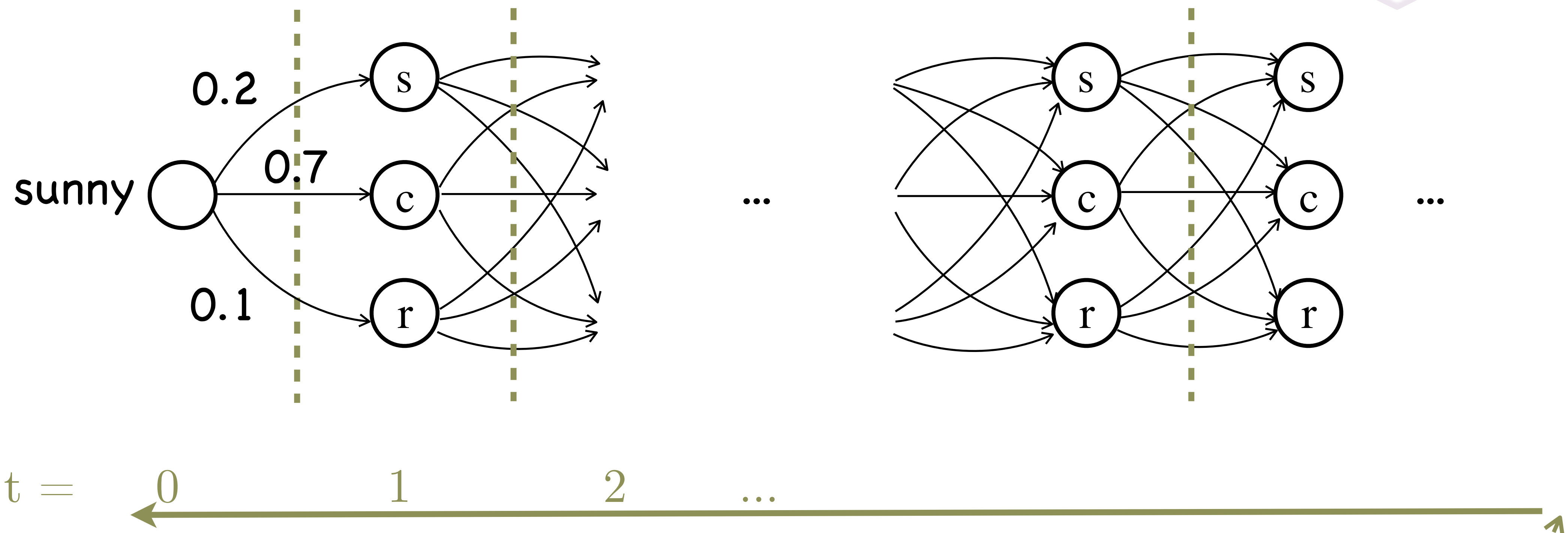
backward calculation

$V(s) = 0$

$$V(s) = \sum_{s'} P(s'|s)\big(R(s') + V(s')\big)$$

Markov Reward Process

horizontal view: consider discounted infinite steps



$V(s) = 0$

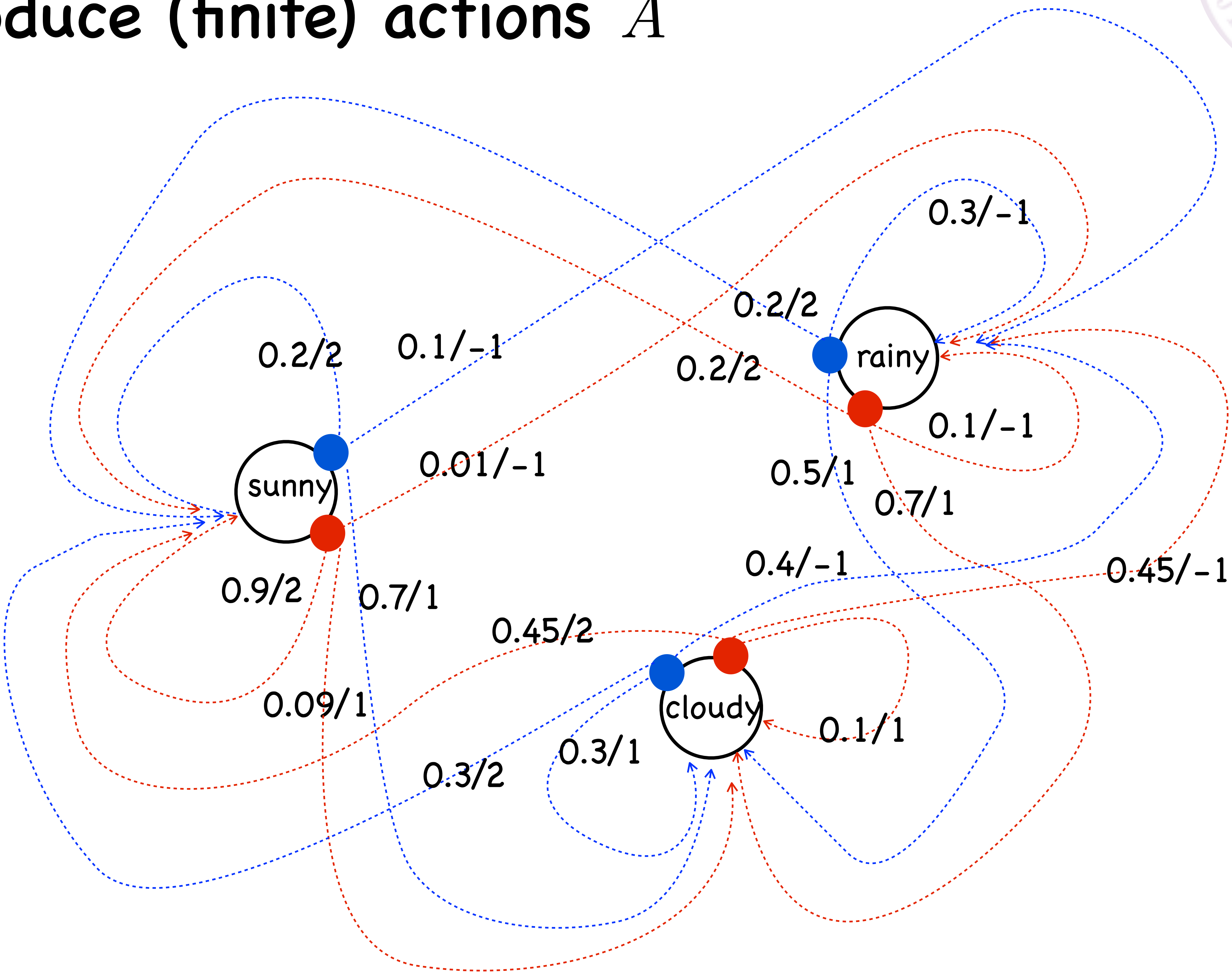
backward calculation

repeat until converges

$$V(s) = \sum_{s'} P(s'|s)\big(R(s') + \gamma V(s')\big)$$

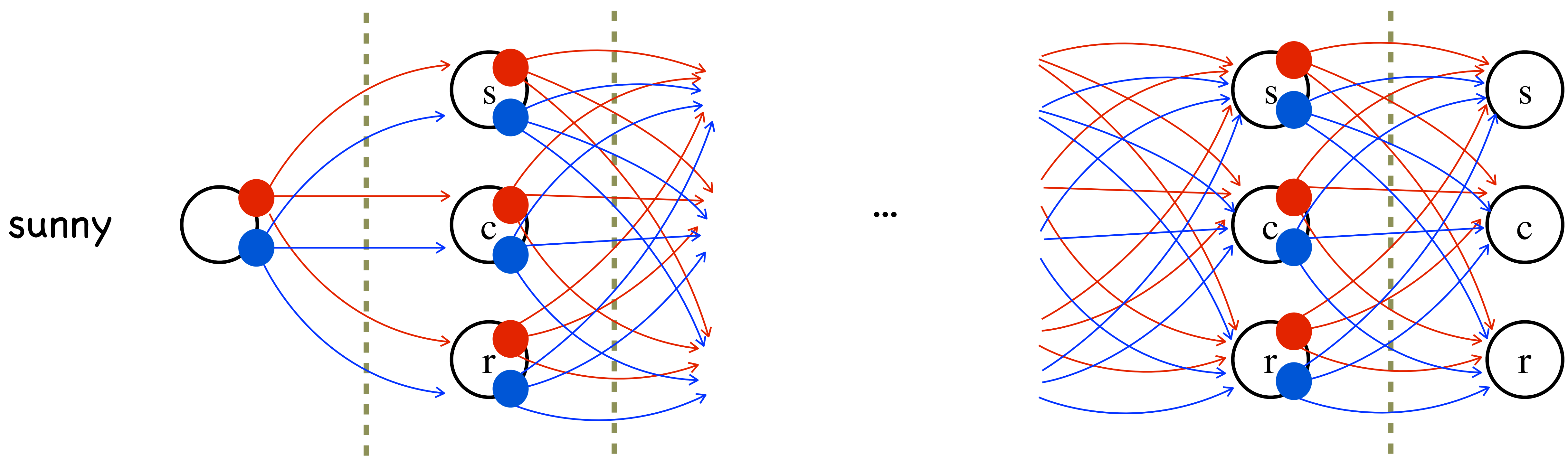
Markov Decision Process

introduce (finite) actions A



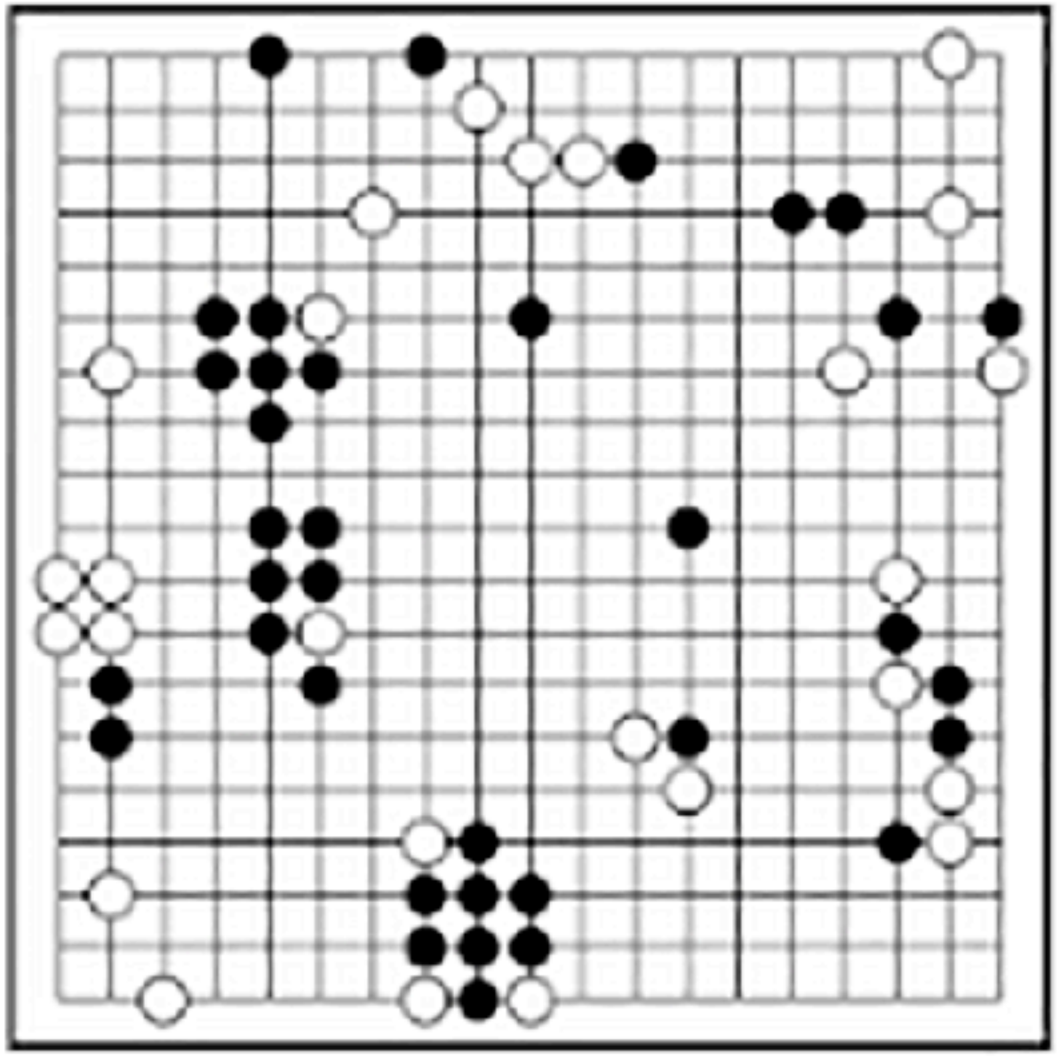
Markov Decision Process

horizontal view



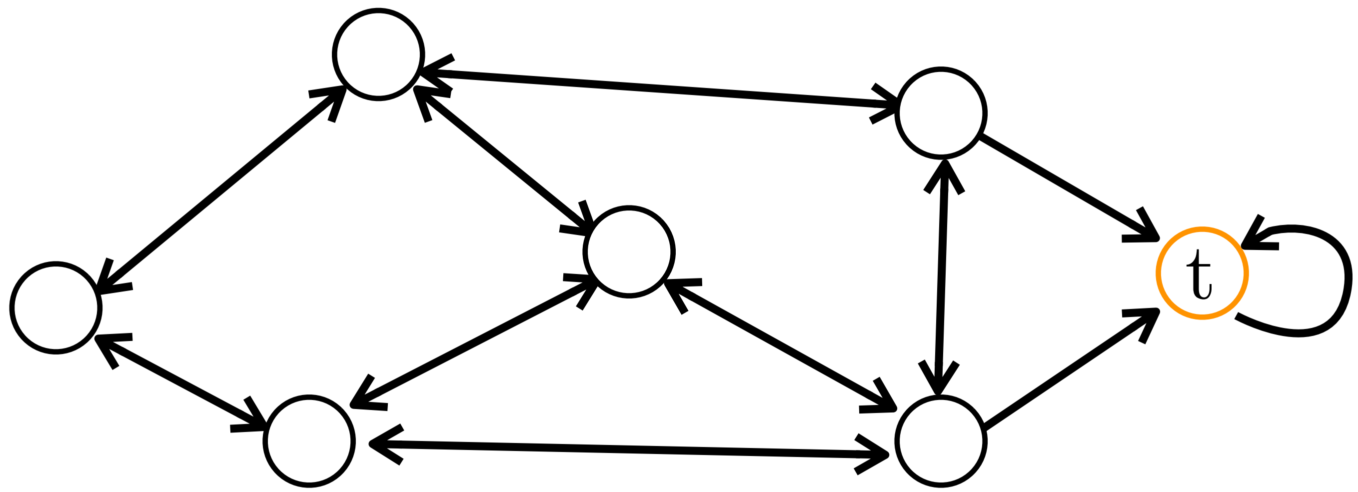
Markov Decision Process

horizontal view of the game of Go

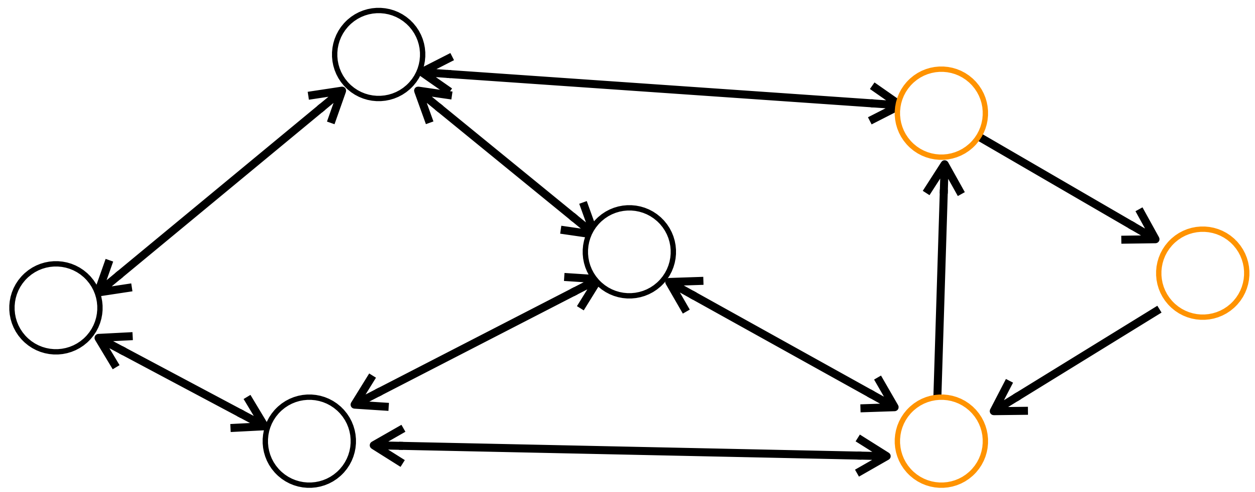


Markov Decision Process

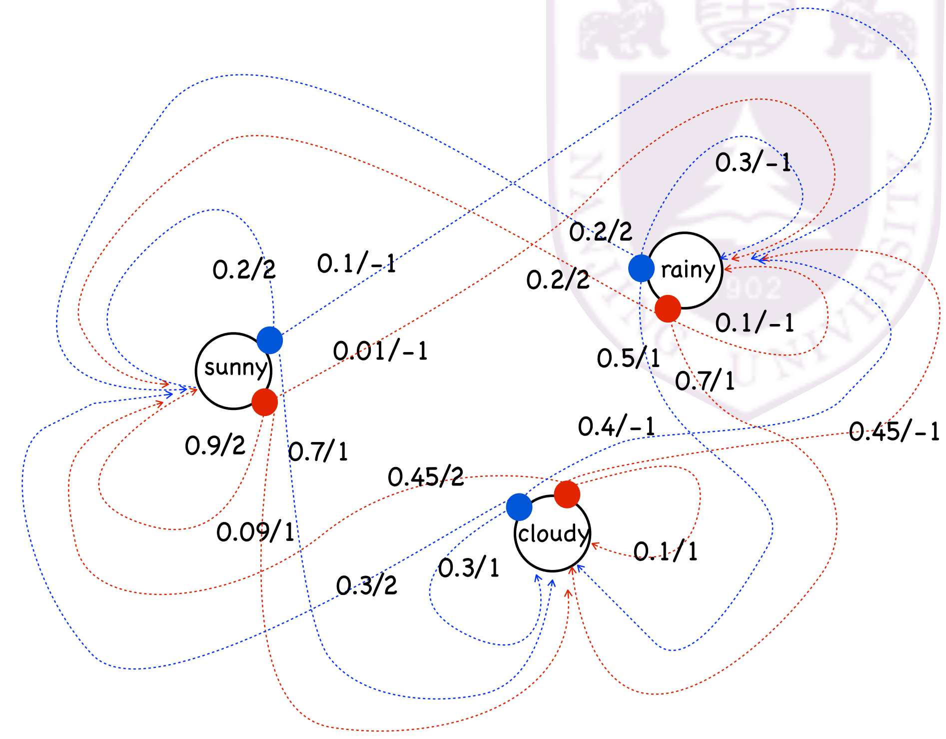
goal-directed



stationary distribution



Markov Decision Process



MDP $<S, A, R, P>$ (often with γ)

essential model for RL

but not all of RL

policy

stochastic

$$\pi(a|s) = P(a|s)$$

deterministic

$$\pi(s) = \arg\max_{a} P(a|s)$$

$|A|^{|S|}$ deterministic policies

tabular representation

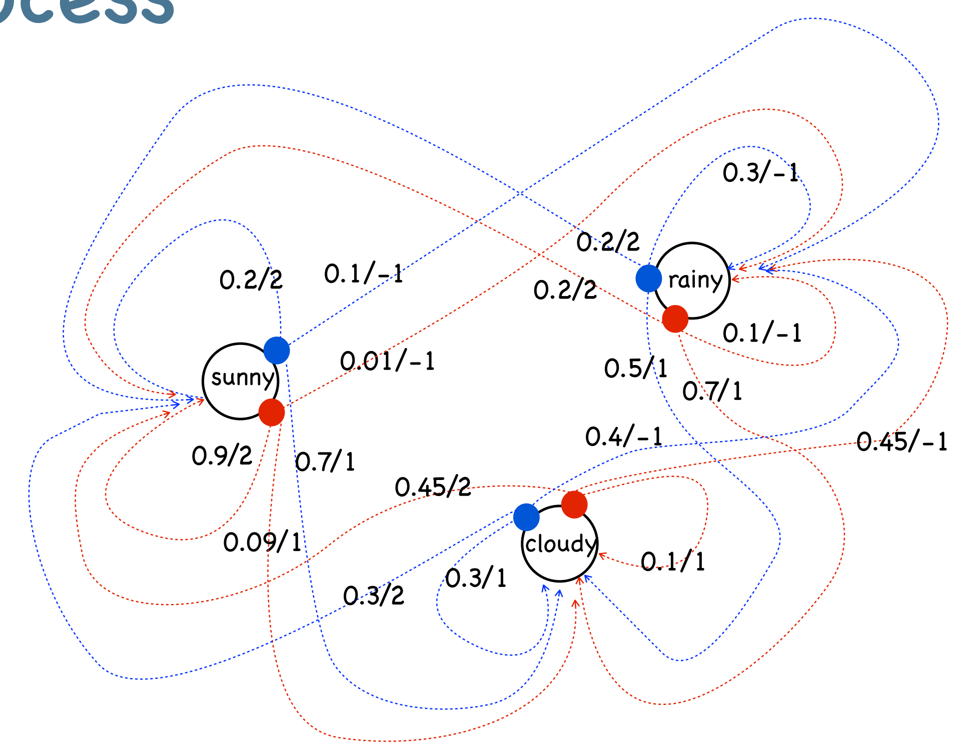
$\pi =$

s	0	0.3
	1	0.7
c	0	0.6
	1	0.4
r	0	0.1
	1	0.9

Expected return

how to calculate the expected total reward of a policy?

similar with the Markov Reward Process



MRP:

$$V(s) = \sum_{s'} P(s'|s)\big(R(s') + V(s')\big)$$

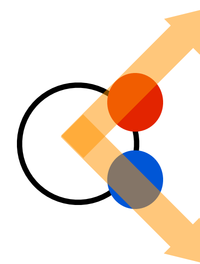
MDP:

$$V^{\pi}(s) = \sum_{a} \pi(a|s) \sum_{s'} P(s'|s,a)\big(R(s,a,s') + V^{\pi}(s')\big)$$

expectation over actions
with respect to the policy

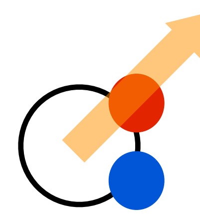
Q-function

state value function



$$V^\pi(s) = E[\sum_{t=1}^{T} r_t | s]$$

state-action value function



$$Q^\pi(s,a) = E[\sum_{t=1}^{T} r_t | s, a] = \sum_{s'} P(s'|s,a)\big(R(s,a,s') + V^\pi(s')\big)$$

consequently,

$$V^\pi(s) = \sum_{a} \pi(a|s) Q(s,a)$$

Q-function => policy

Optimality

s	0	0.3
	1	0.7
c	0	0.6
	1	0.4
r	0	0.1
	1	0.9

there exists an optimal policy π^*

$$\forall \pi, \forall s, V^{\pi^*}(s) \geq V^{\pi}(s)$$

optimal value function

$$\forall s, V^*(s) = V^{\pi^*}(s)$$

$$\forall s, \forall a, Q^*(s,a) = Q^{\pi^*}(s,a)$$

Bellman optimality equations

s	0	0.3
	1	0.7
c	0	0.6
	1	0.4
r	0	0.1
	1	0.9

$$V^*(s) = \max_a Q^*(s,a)$$

from the relation between V and Q

$$Q^*(s,a) = \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma V^*(s')\big)$$

we have

$$Q^*(s,a) = \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma \max_a Q^*(s',a)\big)$$

$$V^*(s) = \max_a \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma V^*(s')\big)$$

the unique fixed point is the optimal value function

Solve optimal policy in MDP

idea:

how is the current policy — policy evaluation

improve the current policy — policy improvement

policy evaluation: backward calculation

$$V^\pi(s) = \sum_a \pi(a|s) \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma V^\pi(s')\big)$$

policy improvement: from the Bellman optimality equation

$$V(s) \leftarrow \max_a Q^\pi(s,a)$$

Solve optimal policy in MDP

policy improvement: from the Bellman optimality equation

$$V(s) \leftarrow \max_a Q^\pi(s,a)$$

let π' be derived from this update

$$\begin{aligned} V^\pi(s) &\le Q^\pi(s, \pi'(s)) \\ &= \sum_{s'} P(s'|s,\pi'(s))(R(s,\pi'(s),s') + \gamma V^\pi(s')) \\ &\le \sum_{s'} P(s'|s,\pi'(s))(R(s,\pi'(s),s') + \gamma Q^\pi(s',\pi'(s))) \\ &= \ldots \\ &= V^{\pi'} \end{aligned}$$

so the policy is improved

Solve optimal policy in MDP

Policy iteration algorithm:

loop until converges

policy evaluation: calculate V

policy improvement: choose the action greedily

$$\pi_{t+1}(s) = \arg\max_a Q^{\pi_t}(s, a)$$

converges: $V^{\pi_{t+1}}(s) = V^{\pi_t}(s)$

$$Q^{\pi_{t+1}}(s, a) = \sum_{s'} P(s'|s, a)\Big(R(s, a, s') + \gamma \max_a Q^{\pi_t}(s', a)\Big)$$

recall the optimal value function about Q

Solve optimal policy in MDP

embed the policy improvement in evaluation

Value iteration algorithm:

$V_0 = 0$

for t=0, 1, …

for all s <- synchronous v.s. asynchronous

$$V_{t+1}(s) = \max_a \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma V_t(s)\big)$$

end for

break if $|| V_{t+1} - V_t ||_\infty$ is small enough

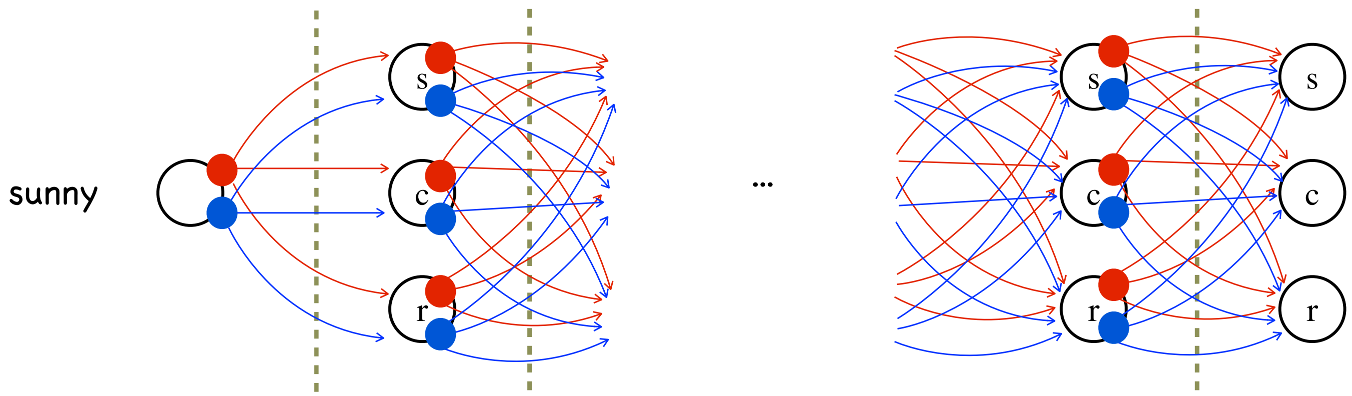
end for

recall the optimal value function about V

Solve optimal policy in MDP

$$Q^{\pi_{t+1}}(s,a) = \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma \max_a Q^{\pi_t}(s',a)\big)$$

$$V_{t+1}(s) = \max_a \sum_{s'} P(s'|s,a)\big(R(s,a,s') + \gamma V_t(s')\big)$$



Dynamic programming

R. E. Bellman
1920-1984

Complexity

needs $\Theta(|S| \cdot |A|)$ iterations to converge on deterministic MDP

[O. Madani. Polynomial Value Iteration Algorithms for Deterministic MDPs. UAI'02]

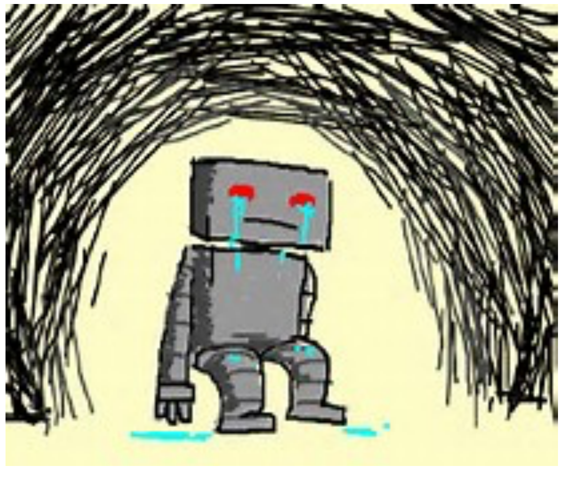
curse of dimensionality: Go board 19x19, $|S|=2.08\times10^{170}$

[https://github.com/tromp/golegal]

from MDP to reinforcement learning

MDP $<S, A, R, P>$

R and P are unknown



Methods

A: learn R and P,

then solve the MDP

model-based

B: learn policy without R or P

model-free

MDP is the model

Model-free RL

explore the environment and learn policy at the same time

Monte-Carlo method

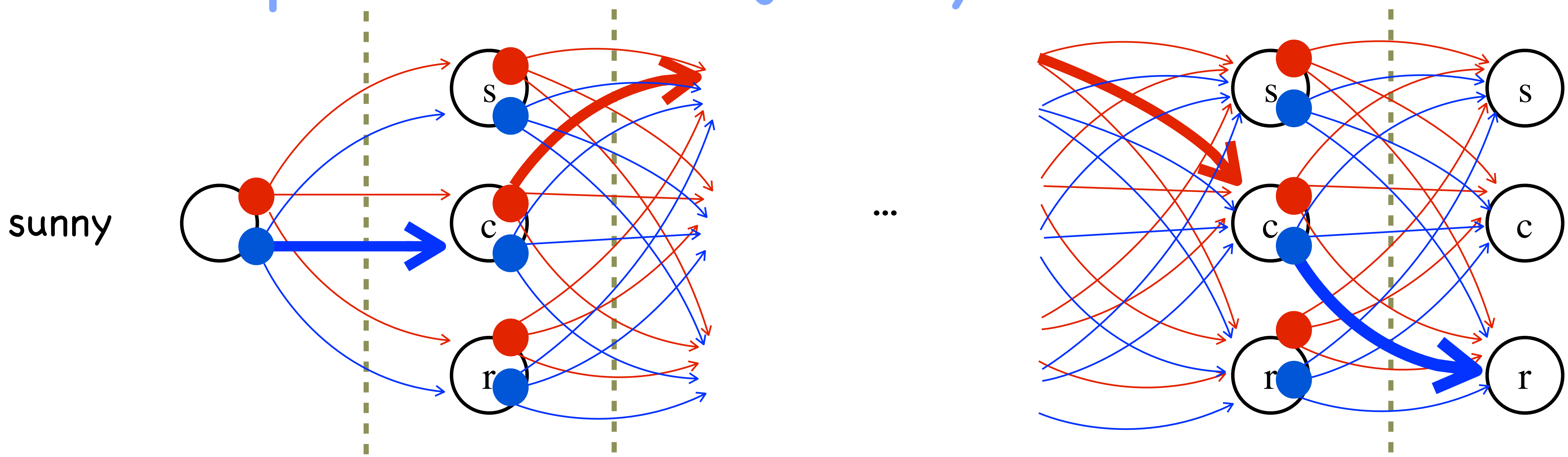
Temporal difference method

Monte Carlo RL - evaluation

Q, not V

expected total reward $Q^\pi(s,a) = E[\sum_{t=1}^{T} r_t | s, a]$

expectation of trajectory-wise rewards



sample trajectory m times,

approximate the expectation by average

$$Q^\pi(s,a) = \frac{1}{m}\sum_{i=1}^{m} R(\tau_i)$$

τ_i **is sample by following** π **after** s, a

Monte Carlo RL - evaluation+improvement

$Q_0 = 0$

for i=0, 1, ..., m

generate trajectory <s_0, a_0, r_1, s_1, ..., s_T>

for t=0, 1, ..., T-1

R = sum of rewards from t to T

$Q(s_t, a_t) = (\mathrm{c}(s_t, a_t)\, Q(s_t, a_t) + \mathrm{R}) / (\mathrm{c}(s_t, a_t) + 1)$

$\mathrm{c}(s_t, a_t){+}{+}$

end for

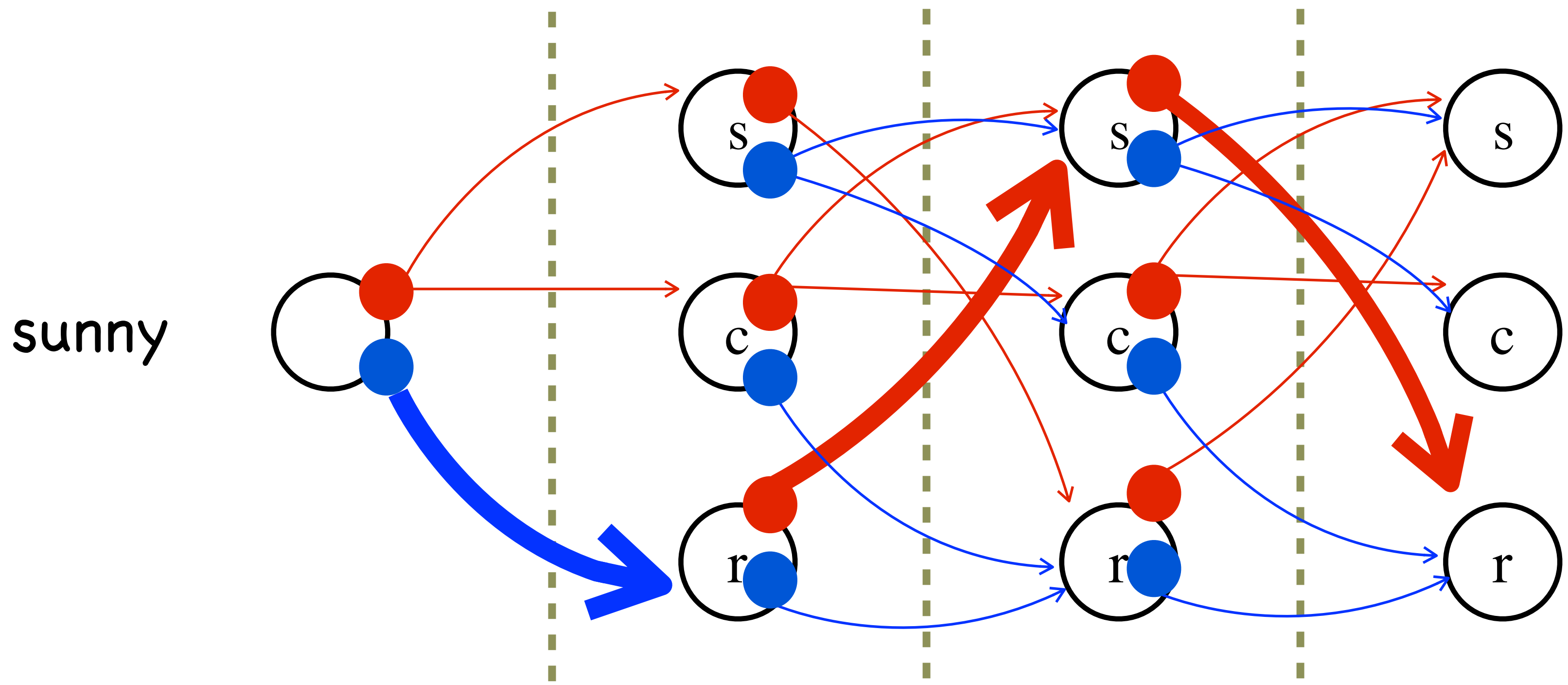
update policy $\pi(s) = \arg\max_a Q(s, a)$

end for

improvement ?

Monte Carlo RL

problem: what if the policy takes only one path?



cannot improve the policy

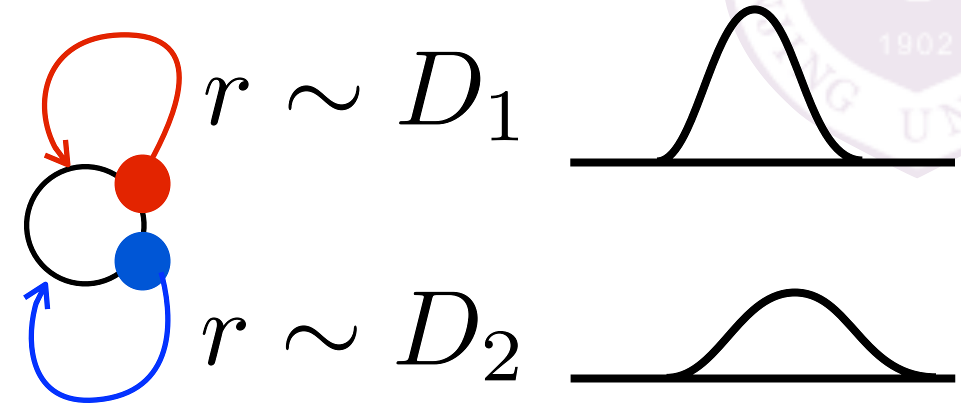
no exploration of the environment

needs exploration !

Exploration methods

one state MDP:

a.k.a. bandit model



maximize the long-term total reward

- exploration only policy: try every action in turn

  waste many trials

- exploitation only policy: try each action once, follow the best action forever

  risk of pick a bad action

balance between exploration and exploitation

Exploration methods

ϵ-greedy:

follow the best action with probability 1-ϵ

choose action randomly with probability ϵ

ϵ should decrease along time

softmax:

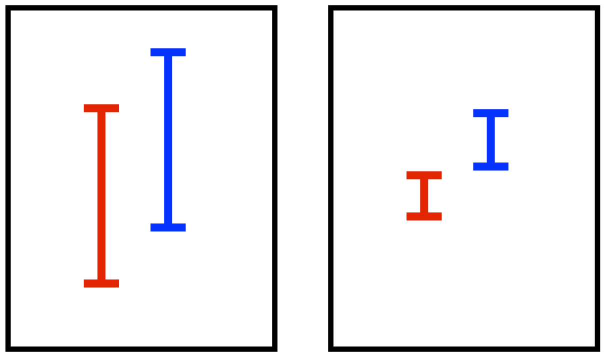
probability according to action quality

$$P(k) = e^{Q(k)/\theta} / \sum_{i=1}^{K} e^{Q(i)/\theta}$$

upper confidence bound (UCB):

choose by action quality + confidence

$$Q(k) + \sqrt{2 \ln n / n_k}$$



Action-level exploration

ϵ-greedy policy:

given a policy π

$$\pi_\epsilon(s) = \begin{cases} \pi(s), \text{with prob. } 1-\epsilon \\ \text{randomly chosen action, with prob. } \epsilon \end{cases}$$

ensure probability of visiting every state > 0

exploration can also be in other levels

Monte Carlo RL

$Q_0 = 0$

for i=0, 1, ..., m

generate trajectory $<s_0, a_0, r_1, s_1, ..., s_T>$ by π_ϵ

for t=0, 1, ..., T-1

R = sum of rewards from t to T

$Q(s_t, a_t) = (\mathrm{c}(s_t, a_t) Q(s_t, a_t) + \mathrm{R}) / (\mathrm{c}(s_t, a_t) + 1)$

$\mathrm{c}(s_t, a_t)$++

end for

update policy $\pi(s) = \arg\max_a Q(s, a)$

end for

Monte Carlo RL - on/off-policy

this algorithm evaluates π_ϵ ! on-policy

what if we want to evaluate π ? off-policy

importance sampling:

$$E[f] = \int_x p(x) f(x) \mathrm{d}x = \int_x q(x) \frac{p(x)}{q(x)} f(x) \mathrm{d}x$$

↓ sample from p ↓ sample from q

$$\frac{1}{m} \sum_{i=1}^{m} f(x) \qquad \frac{1}{m} \sum_{i=1}^{m} \frac{p(x)}{q(x)} f(x)$$

Monte Carlo RL -- off-policy

$Q_0 = 0$

for i=0, 1, ..., m

generate trajectory $<s_0, a_0, r_1, s_1, ..., s_T>$ by π_ϵ

for t=0, 1, ..., T-1

R = sum of rewards from t to $T \times \prod_{i=t+1}^{T-1} \frac{\pi(x_i, a_i)}{p_i}$

$Q(s_t, a_t) = (\mathrm{c}(s_t, a_t) Q(s_t, a_t) + \mathrm{R}) / (\mathrm{c}(s_t, a_t) + 1)$

$\mathrm{c}(s_t, a_t)$++

end for

update policy $\pi(s) = \arg\max_a Q(s, a)$

end for

$$p_i = \begin{cases} 1 - \epsilon + \epsilon/|A|, a_i = \pi(s_i), \\ \epsilon/|A|, a_i \neq \pi(s_i) \end{cases}$$

Monte Carlo RL

summary

Monte Carlo evaluation:
approximate expectation by sample average

action-level exploration

on-policy, off-policy: importance sampling

Monte Carlo RL:
evaluation + action-level exploration + policy improvement (on/off-policy)

Incremental mean

$$Q(s_t, a_t) = (\mathrm{c}(s_t, a_t)\, Q(s_t, a_t) + \mathrm{R}) / (\mathrm{c}(s_t, a_t) + 1)$$

$$\mu_t = \frac{1}{t}\sum_{i=1}^{t} x_i = \frac{1}{t}(x_t + \sum_{i=1}^{t-1} x_i) = \frac{1}{t}(x_t + (t-1)\mu_{t-1})$$

$$= \mu_{t-1} + \frac{1}{t}(x_t - \mu_{t-1})$$

In general, $\mu_t = \mu_{t-1} + \alpha(x_t - \mu_{t-1})$

Monte-Carlo update:

$$Q(s_t, a_t) \Leftarrow Q(s_t, a_t) + \alpha(\underbrace{R - Q(s_t, a_t))}_{\text{MC error}}$$

Temporal-Difference Learning - evaluation

update policy online learn as you go

TD Evaluation

Monte-Carlo update:

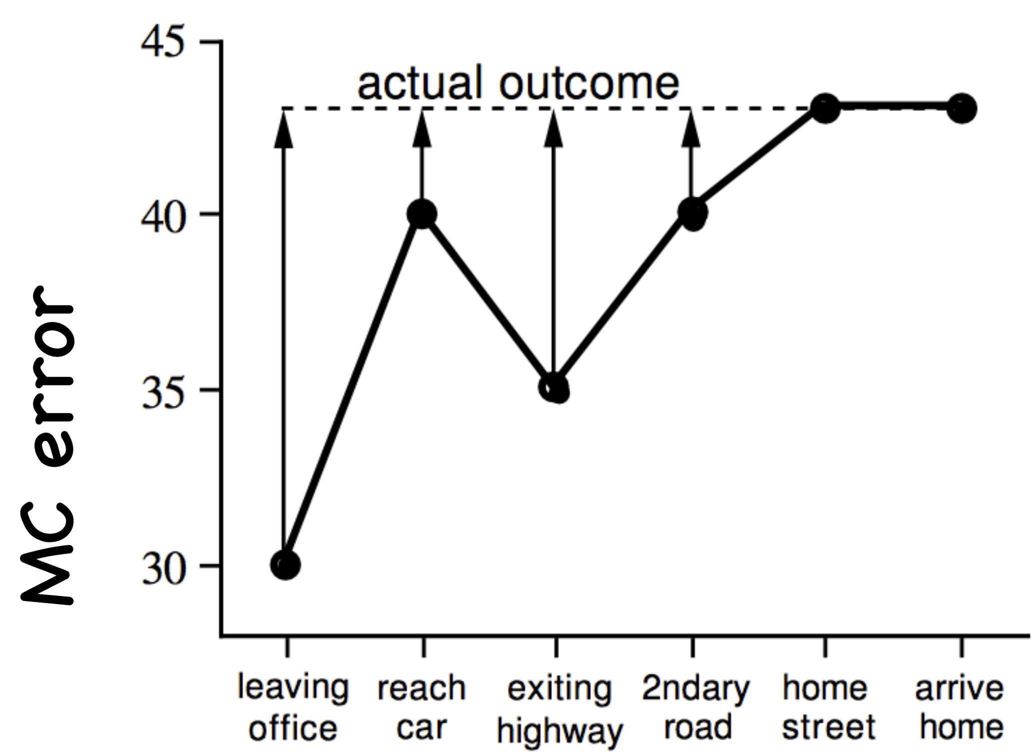
$$Q(s_t, a_t) \Leftarrow Q(s_t, a_t) + \alpha\underbrace{(R - Q(s_t, a_t))}_{\text{MC error}}$$

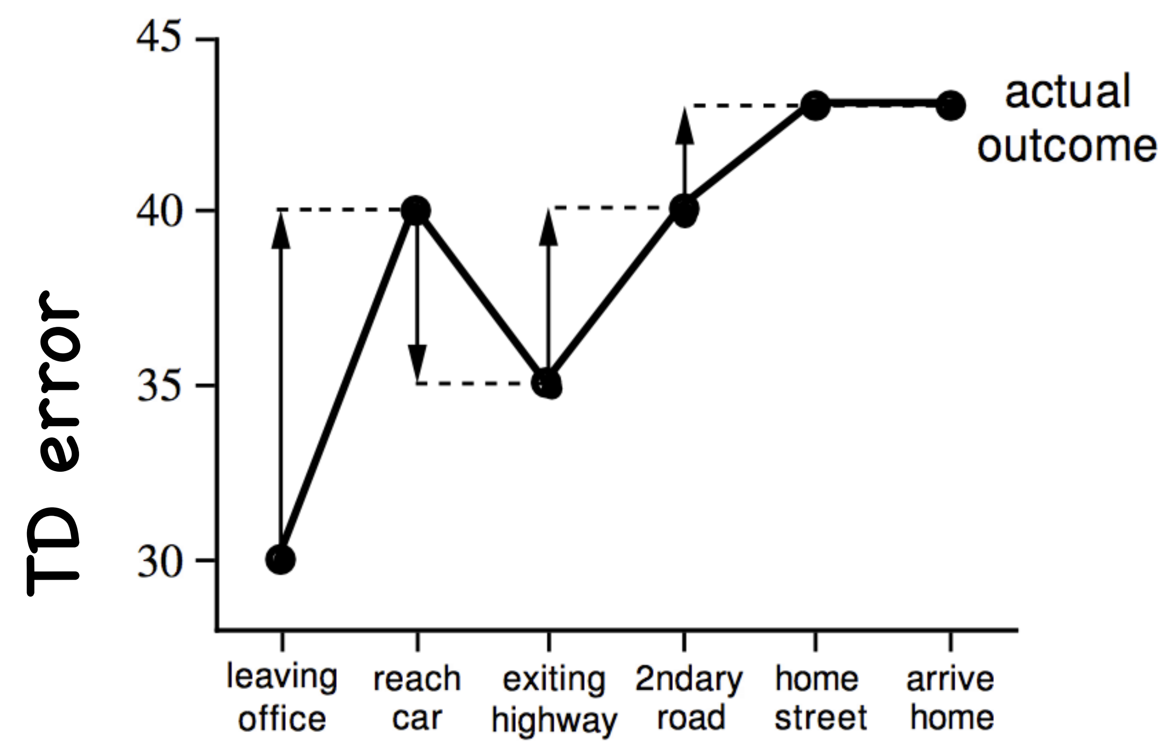
TD update:

$$Q(s_t, a_t) \Leftarrow Q(s_t, a_t) + \alpha\underbrace{(r_{t+1} + \gamma Q(s_{t+1}, a_{t+1}) - Q(s_t, a_t))}_{\text{TD error}}$$

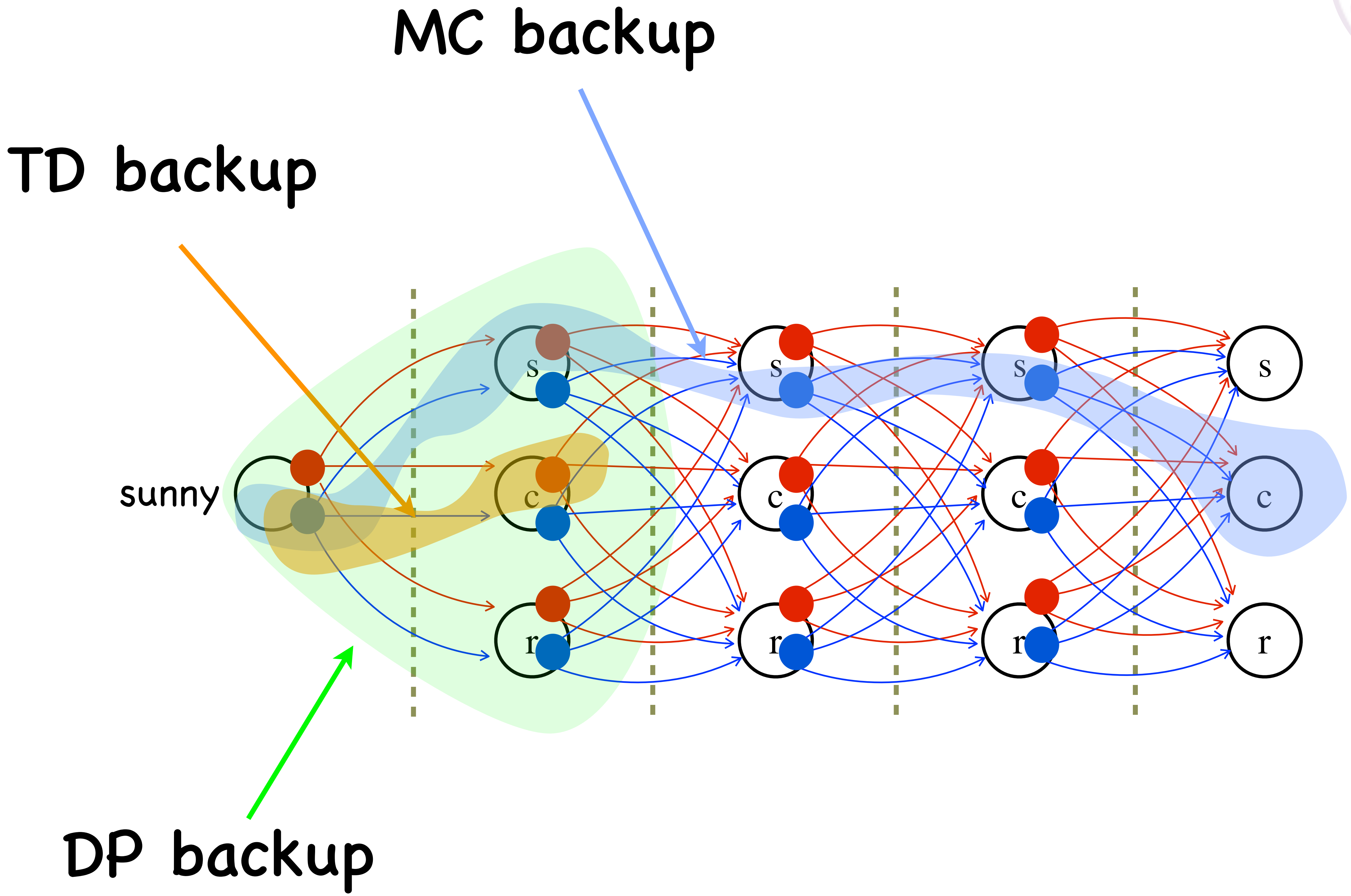
Temporal-Difference Learning - example

state	elapsed time	predicted remaining time	predicted total time
leaving office	0	30	30
reach car, raining	5	35	40
exit highway	20	15	35
behind truck	30	10	40
home street	40	3	43
arrive home	43	0	43





Temporal-Difference Learning - backups



SARSA

On-policy TD control

$Q_0 = 0$, initial state
for i=0, 1, ...
$a = \pi_\epsilon(s)$
s', r = do action a
$a' = \pi_\epsilon(s')$
$Q(s,a) \mathrel{+}= \alpha(r + \gamma Q(s',a') - Q(s,a))$
$\pi(s) = \arg\max_a Q(s,a)$
$s = s'$
end for

Q-learning

Off-policy TD control

$Q_0 = 0$, initial state

for i=0, 1, ...

$a = \pi_\epsilon(s)$

s', r = do action a

$a' = \pi(s')$

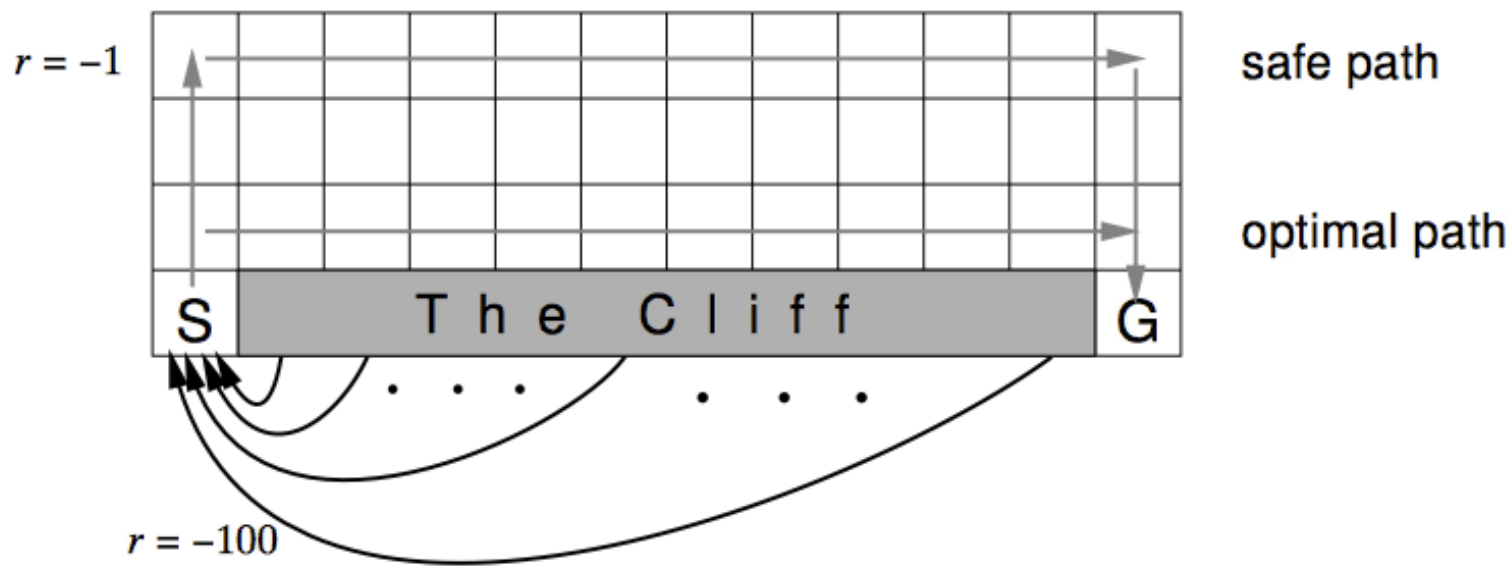
$Q(s,a) \mathrel{+}= \alpha(r + \gamma Q(s',a') - Q(s,a))$

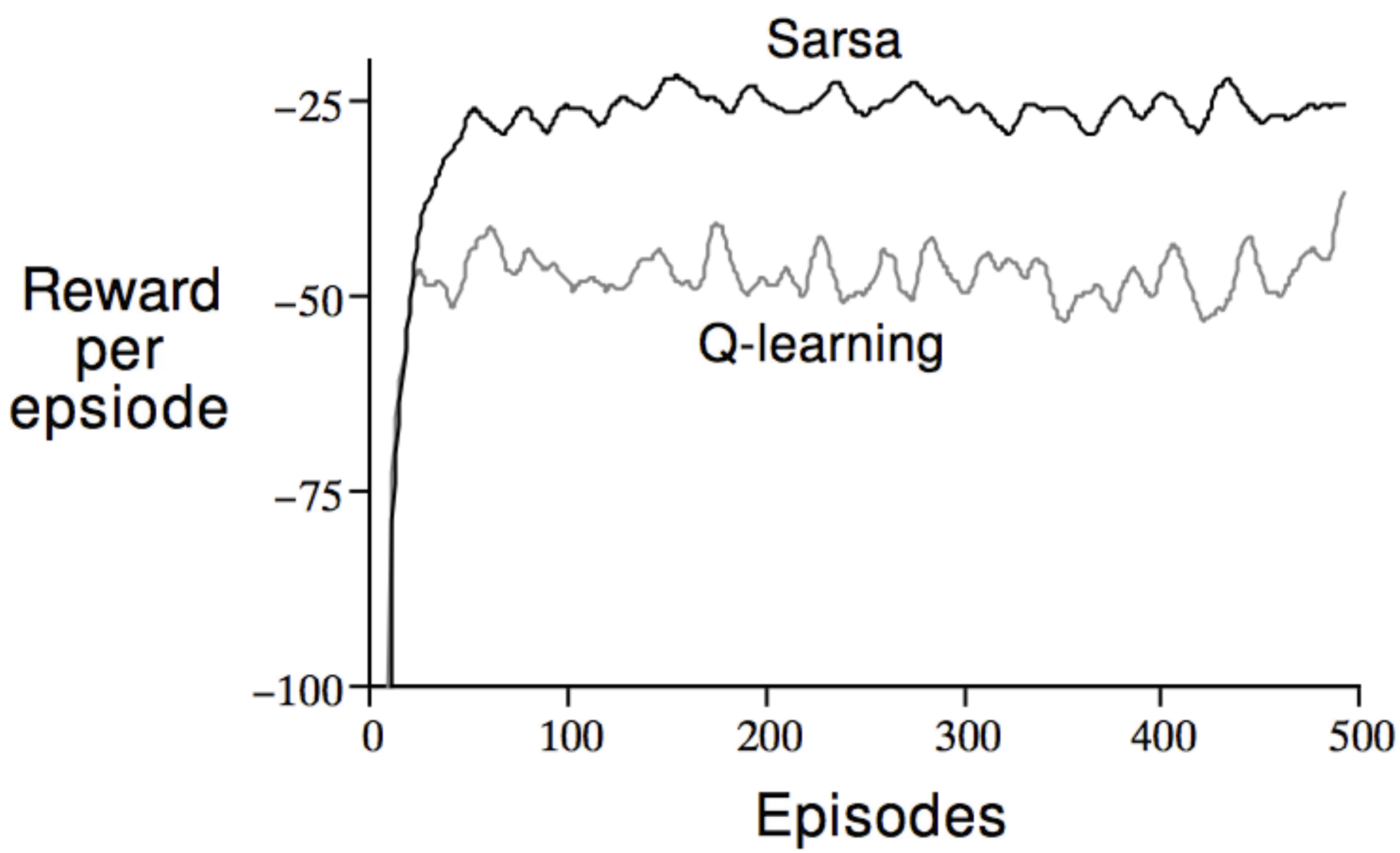
$\pi(s) = \arg\max_a Q(s,a)$

$s = s'$

end for

SARSA v.s. Q-learning



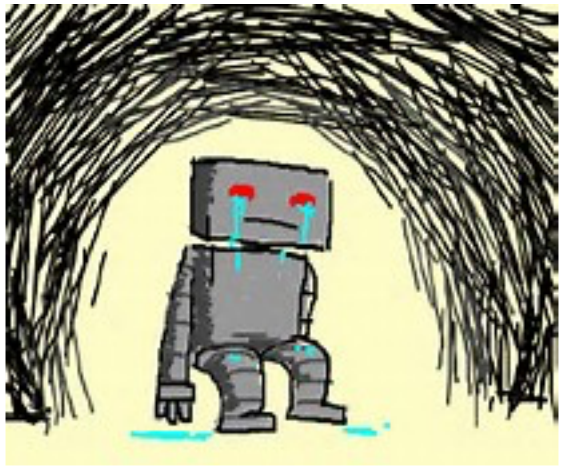


we can do RL now! ... in (small) discrete state space

RL in continuous state space

MDP $<S, A, R, P>$

S **(and** A**) is in** $\mathbb{R}^n$



Value function approximation

modern RL

tabular representation

$\pi =$

s	0	0.3
	1	0.7
c	0	0.6
	1	0.4
r	0	0.1
	1	0.9

very powerful representation

can be all possible policies !

linear function approx.

$$\hat{V}(s) = w^\top \phi(s)$$

$$\hat{Q}(s,a) = w^\top \phi(s,a)$$

$$\hat{Q}(s,a_i) = w_i^\top \phi(s)$$

ϕ is a feature mapping

w is the parameter vector

may not represent all policies !

Value function approximation

to approximate Q and V value function

least square approximation

$$J(w) = E_{s\sim\pi}[(Q^{\pi}(s,a) - \hat{Q}(s,a))^2]$$

online environment: stochastic gradient on single sample

$$\Delta w_t = \theta(Q^{\pi}(s_t,a_t) - \hat{Q}(s_t,a_t))\nabla_w \hat{Q}(s_t,a_t)$$

replace

Recall the errors:

MC update: $Q(s_t,a_t) += \alpha(R - Q(s_t,a_t))$

TD update: $Q(s_t,a_t) += \alpha(r_{t+1} + \gamma Q(s_{t+1},a_{t+1}) - Q(s_t,a_t))$

target model

Value function approximation

MC update:

$$\Delta w_t = \theta(R - \hat{Q}(s_t, a_t))\nabla_w \hat{Q}(s_t, a_t)$$

TD update:

$$\Delta w_t = \theta(r_{t+1} + \gamma \hat{Q}(s_{t+1}, a_{t+1}) - \hat{Q}(s_t, a_t))\nabla_w \hat{Q}(s_t, a_t)$$

eligibility traces

$$E_t = \gamma \lambda E_{t-1} + \nabla_w \hat{Q}(s_t, a_t)$$

Q-learning with function approximation

$w = 0$, initial state

for i=0, 1, ...

$a = \pi_\epsilon(s)$

s', r = do action a

a' $= \pi(s')$

$w += \theta(r + \gamma\hat{Q}(s,a) - \hat{Q}(s,a))\nabla_w\hat{Q}(s_t,a_t)$

$\pi(s) = \arg\max_a \hat{Q}(s,a)$

$s = s$'

end for

Approximation model

Linear approximation $\hat{Q}(s,a) = w^\top \phi(s,a)$

$$\nabla_w \hat{Q}(s,a) = \phi(s,a)$$

coarse coding: raw features

discretization: tide with indicator features

kernelization:

$$\hat{Q}(s,a) = \sum_{i=1}^{m} w_i K((s,a),(s_i,a_i))$$

(s_i, a_i) can be randomly sampled

Approximation model

Nonlinear model approximation $\hat{Q}(s,a) = f(s,a)$

neural network: differentiable model

recall the TD update:

$$\Delta w_t = \theta(r_{t+1} + \gamma \hat{Q}(s_{t+1}, a_{t+1}) - \hat{Q}(s_t, a_t)) \underline{\nabla_w \hat{Q}(s_t, a_t)}$$

follow the BP rule to pass the gradient

Batch RL methods

gradient on single sample introduces large variance

Batch mode evaluation:

collect trajectory and history data

$$D = \{(s_1, V_1^\pi), (s_2, V_2^\pi), \ldots, (s_m, V_m^\pi)\}$$

solve batch least square objective

$$J(w) = E_D[\big(V^\pi - \hat{V}(s)\big)^2]$$

linear function: closed form

neural networks: batch update/repeated stochastic update

LSMC, LSTD, LSTD(λ)

Batch RL methods

gradient on single sample introduces large variance

Batch mode policy iteration: LSPI

$Q_0 = 0$, initial state

for i=0, 1, ...

collect data D

$$w = \arg\min_w \sum_{(s,a)\in D} (r + \gamma \hat{Q}(s,\pi(s)) - \hat{Q}(s,a))\phi(s,a)$$

$$\forall s, \pi(s) = \arg\max_a Q(s,a)$$

end for

Robot Motor Skill Coordination with EM-based Reinforcement Learning

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