Reinforcement Learning Part 2

CS 760@UW-Madison

Goals for the lecture

you should understand the following concepts

- value functions and value iteration (review)
- Q functions and Q learning (review)
- exploration vs. exploitation tradeoff
- compact representations of Q functions
- reinforcement learning example

Value function for a policy

- given a policy $\pi : S \rightarrow A$ define

$$V^{\pi}(s) = \sum_{t=0}^{\infty} \gamma^t E[r_t]$$

assuming action sequence chosen according to π starting at state s

- we want the optimal policy π^* where

$$p^* = \arg\max_p V^p(s) \quad \text{for all } s$$

we'll denote the value function for this optimal policy as $V^*(s)$

Value iteration for learning $V^*(s)$

initialize $V(s)$ arbitrarily

loop until policy good enough

{

  loop for $s \in S$

  {

    loop for $a \in A$

    {

$$Q(s,a) \leftarrow r(s,a) + \gamma \sum_{s' \in S} P(s' | s,a) V(s')$$

    }

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

  }

}

Q learning

define a new function, closely related to V^*

$$V^*(s) \leftarrow E\left[r(s,\pi^*(s))\right] + \gamma E_{s'|s,\pi^*(s)}\left[V^*(s')\right]$$

$$Q(s,a) \leftarrow E\left[r(s,a)\right] + \gamma E_{s'|s,a}\left[V^*(s')\right]$$

if agent knows $Q(s, a)$, it can choose optimal action without knowing $P(s' \mid s, a)$

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

and it can learn $Q(s, a)$ without knowing $P(s' \mid s, a)$

Q learning for deterministic worlds

for each s, a initialize table entry $\hat{Q}(s,a) \leftarrow 0$

observe current state s

do forever

select an action a and execute it

receive immediate reward r

observe the new state s'

update table entry

$$\hat{Q}(s,a) \leftarrow r + \gamma \max_{a'} \hat{Q}(s',a')$$

$s \leftarrow s'$

Q learning for *nondeterministic* worlds

for each s, a initialize table entry $\hat{Q}(s,a) \leftarrow 0$

observe current state s

do forever

- select an action a and execute it
- receive immediate reward r
- observe the new state s'
- update table entry

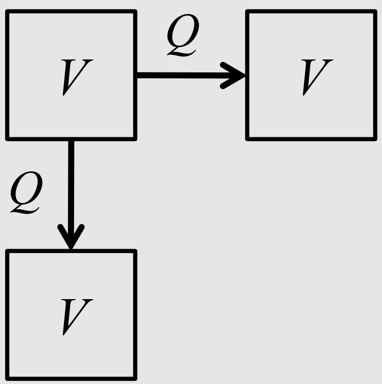
$$\hat{Q}_n(s,a) \leftarrow (1-\alpha_n)\hat{Q}_{n-1}(s,a) + \alpha_n \left[r + \gamma \max_{a'} \hat{Q}_{n-1}(s',a') \right]$$

- $s \leftarrow s'$

where α_n is a parameter dependent on the number of visits to the given (s, a) pair

$$a_n = \frac{1}{1 + \text{visits}_n(s,a)}$$

Q's vs. V's



- Which action do we choose when we're in a given state?
- V's (model-based)
  - need to have a 'next state' function to generate all possible states
  - choose next state with highest V value.
- Q's (model-free)
  - need only know which actions are legal
  - generally choose next state with highest Q value.

Exploration vs. Exploitation

- in order to learn about better alternatives, we shouldn't always follow the current policy (exploitation)
- sometimes, we should select random actions (exploration)
- one way to do this: select actions probabilistically according to:

$$P(a_i \mid s) = \frac{c^{\hat{Q}(s, a_i)}}{\sum_j c^{\hat{Q}(s, a_j)}}$$

where $c > 0$ is a constant that determines how strongly selection favors actions with higher Q values

Q learning with a table

As described so far, Q learning entails filling in a huge table

states

actions

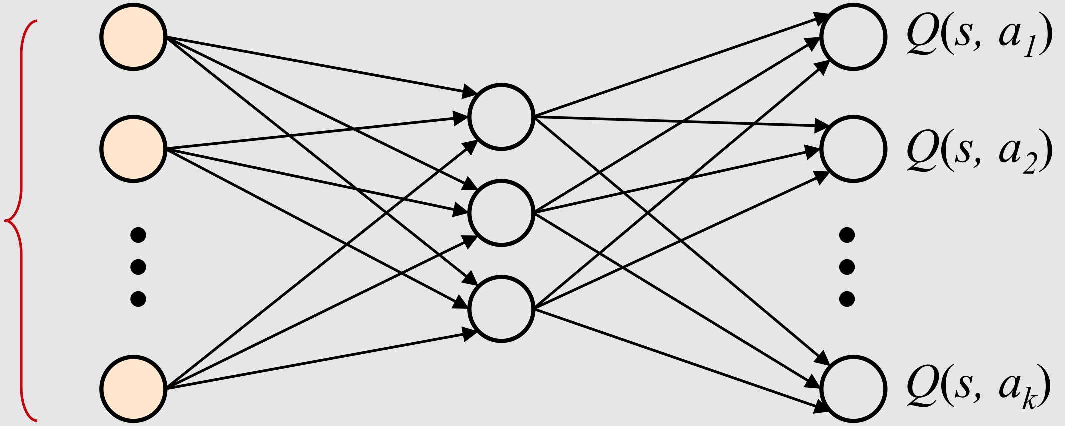
$$\begin{array}{c|cccccc} & s_0 & s_1 & s_2 & & \cdots & s_n \\ \hline a_1 & & & \vdots & & & \\ a_2 & & & & & & \\ a_3 & \cdots & & Q(s_2, a_3) & & & \\ \vdots & & & & & & \\ a_k & & & & & & \end{array}$$

A table is a very <u>verbose way to</u> represent a function

Representing Q functions more compactly

We can use some other function representation (e.g. a neural net) to <u>compactly</u> encode a substitute for the big table

encoding of the state (s)



each input unit encodes a property of the state (e.g., a sensor value)

or could have <u>one net</u> for <u>each</u> possible action

Why use a compact Q function?

1. Full Q table may not fit in memory for realistic problems
2. Can generalize across states, thereby speeding up convergence

   i.e. one instance 'fills' many cells in the Q table

Notes

1. When generalizing across states, cannot use $\alpha=1$
2. Convergence proofs only apply to Q tables
3. Some work on bounding errors caused by using compact representations (e.g. Singh & Yee, *Machine Learning* 1994)

Q tables vs. Q nets

Given: 100 Boolean-valued features

10 possible actions

Size of Q table

10×2^{100} entries

Size of Q net (assume 100 hidden units)

$$\underbrace{100 \times 100}_{\text{weights between inputs and HU's}} + \underbrace{100 \times 10}_{\text{weights between HU's and outputs}} = 11{,}000 \text{ weights}$$

Representing Q functions more compactly

- we can use other regression methods to represent Q functions
  - k-NN
  - regression trees
  - support vector regression
  - etc.

Q learning with function approximation

1. measure sensors, sense state s_0
2. predict $\hat{Q}_n(s_0, a)$ for each action a
3. select action a to take (with randomization to ensure exploration)
4. apply action a in the real world
5. sense new state s_1 and immediate reward r
6. calculate action a' that maximizes $\hat{Q}_n(s_1, a')$
7. train with new instance

$$\boldsymbol{x} = s_0$$

$$y \leftarrow (1-\alpha)\hat{Q}(s_0, a) + \alpha\left[r + \gamma \max_{a'} \hat{Q}(s_1, a')\right]$$

Calculate Q-value you would have put into Q-table, and use it as the training label

ML example: reinforcement learning to control an autonomous helicopter

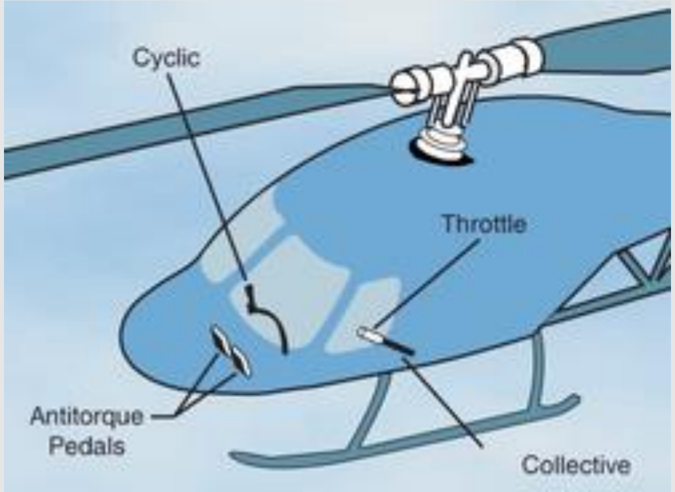
video of Stanford University autonomous helicopter from http://heli.stanford.edu/

Stanford autonomous helicopter

sensing the helicopter's state

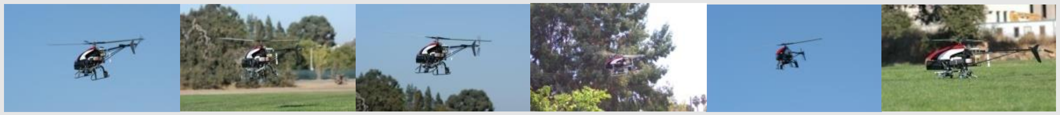
- orientation sensor
  - accelerometer
  - rate gyro
  - magnetometer
- GPS receiver ("2cm accuracy as long as its antenna is pointing towards the sky")
- ground-based cameras

actions to control the helicopter

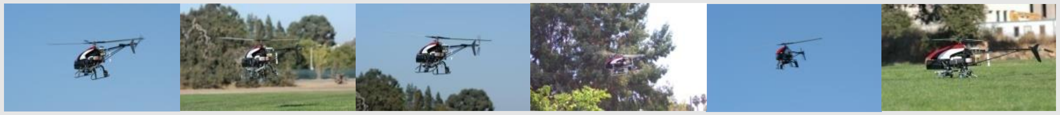


Experimental setup for helicopter

1. Expert pilot demonstrates the airshow several times



2. Learn a reward function based on desired trajectory
3. Learn a dynamics model
4. Find the optimal control policy for learned reward and dynamics model
5. Autonomously fly the airshow



6. Learn an improved dynamics model. Go back to step 4

Learning dynamics model $P(s_{t+1} \mid s_t,\ a)$

- state represented by helicopter's

position (x, y, z)

velocity $(\dot{x}, \dot{y}, \dot{z})$

angular velocity (w_x, w_y, w_z)

- action represented by manipulations of 4 controls

$$(u_1, u_2, u_3, u_4)$$

- dynamics model predicts accelerations as a function of current state and actions
- accelerations are integrated to compute the predicted next state

Learning dynamics model $P(s_{t+1} \mid s_t, a)$

dynamics model

$$\ddot{x}^b = A_x \dot{x}^b + g_x^b + w_x,$$
$$\ddot{y}^b = A_y \dot{y}^b + g_y^b + D_0 + w_y,$$
$$\ddot{z}^b = A_z \dot{z}^b + g_z^b + C_4 u_4 + D_4 + w_z,$$
$$\dot{\omega}_x^b = B_x \omega_x^b + C_1 u_1 + D_1 + w_{\omega_x},$$
$$\dot{\omega}_y^b = B_y \omega_y^b + C_2 u_2 + D_2 + w_{\omega_y},$$
$$\dot{\omega}_z^b = B_z \omega_z^b + C_3 u_3 + D_3 + w_{\omega_z}.$$

- A, B, C, D represent model parameters
- g represents gravity vector
- w's are random variables representing noise and unmodeled effects

- linear regression task!

Learning a desired trajectory

- repeated expert demonstrations are often suboptimal in different ways
- given a set of M demonstrated trajectories

$$y_j^k = \begin{bmatrix} s_j^k \\ u_j^k \end{bmatrix} \quad \text{for } j = 0,\ldots,N-1, k = 0,\ldots,M-1$$

action on j^{th} step of trajectory k

state on j^{th} step of trajectory k

- try to infer the implicit desired trajectory

$$z_t = \begin{bmatrix} s_t^* \\ u_t^* \end{bmatrix} \quad \text{for } t = 0,\ldots,H$$

Learning a desired trajectory

colored lines: demonstrations of two loops
black line: inferred trajectory

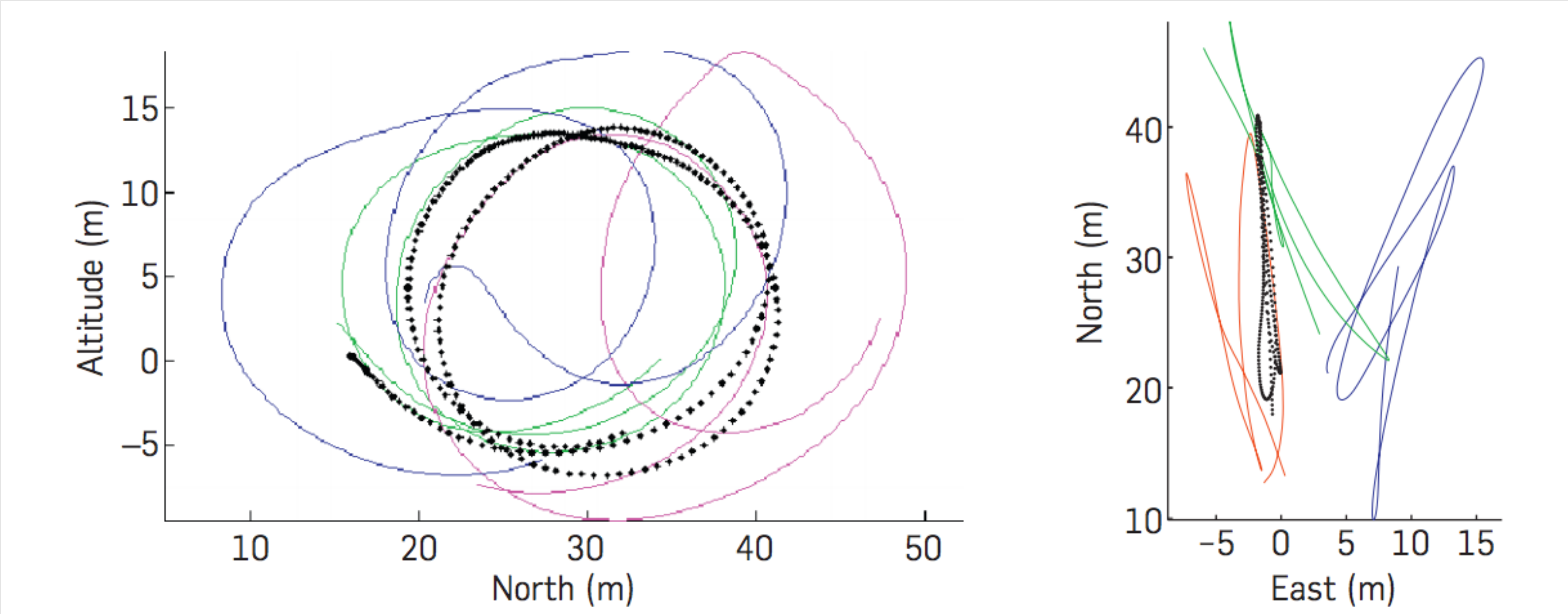


Figure from Coates et al.,*CACM* 2009

Learning reward function

- EM is used to infer desired trajectory from set of demonstrated trajectories

- The reward function is based on deviations from the desired trajectory

Finding the optimal control policy

- finding the control policy is a reinforcement learning task

$$\pi^* \leftarrow \arg\max_\pi E\left[\sum_t r(s_t, a) \mid \pi\right]$$

- RL learning methods described earlier don't quite apply because state and action spaces are both continuous
- A special type of Markov decision process in which the optimal policy can be found efficiently
  - reward is represented as a linear function of state and action vectors
  - next state is represented as a linear function of current state and action vectors
- They use an iterative approach that finds an approximate solution because the reward function used is quadratic

THANK YOU

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