CS 471/571(Fall 2023): Introduction to Artificial Intelligence

Lecture 14: Reinforcement Learning (Part 3)

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Source: http://ai.berkeley.edu/home.html

Reminder

- Written assignment 3: MDPs and Reinforcement Learning
  - Deadline: Nov 08th, 2023

Reinforcement Learning

- We still assume an MDP:
  - A set of states $s \in S$
  - A set of actions (per state) A
  - A model $T(s,a,s')$
  - A reward function $R(s,a,s')$
- Still looking for a policy $\pi(s)$

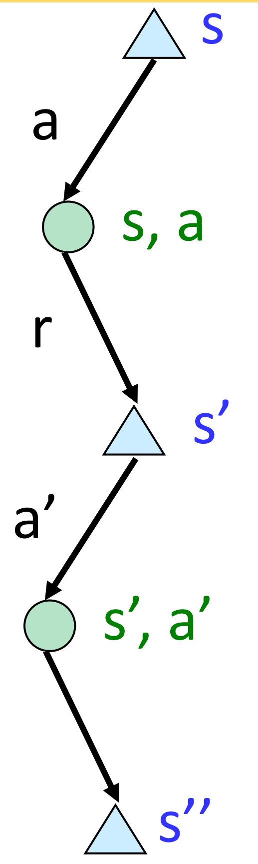
- New twist: don't know T or R, so must try out actions
- Big idea: Compute all averages over T using sample outcomes

Model-Free Learning

- Model-free (temporal difference) learning
  - Experience world through episodes

$$(s, a, r, s', a', r', s'', a'', r'', s'''' \ldots)$$

  - Update estimates each transition (s, a, r, s')
  - Over time, updates will mimic Bellman updates



Q-Learning

- We'd like to do Q-value updates to each Q-state:

$$Q_{k+1}(s,a) \leftarrow \sum_{s'} T(s,a,s') \left[R(s,a,s') + \gamma \max_{a'} Q_k(s',a')\right]$$

  - But can't compute this update without knowing T, R

- Instead, compute average as we go
  - Receive a sample transition (s,a,r,s')
  - This sample suggests

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

  - But we want to average over results from (s,a) (Why?)
  - So keep a running average

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

Example

- Two states: A, B
- Two actions: Up, Down
- Discount factor: $\gamma = 0.5$
- Learning rate: $\alpha = 0.5$
- Q(A, Down) = ?
- Q(B, Up) = ?

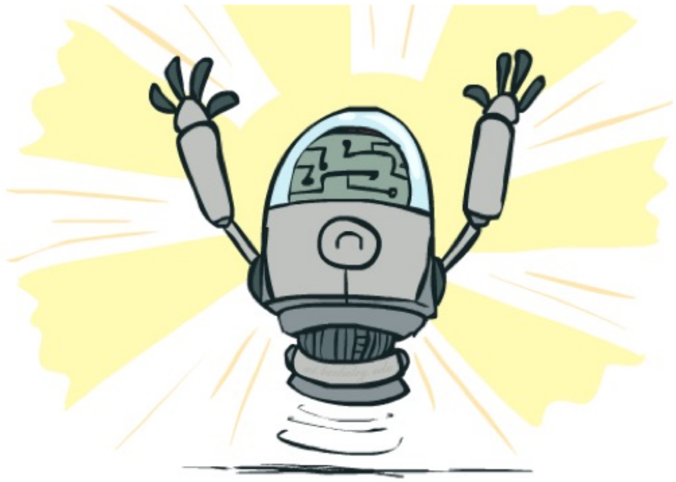
t	s_t	a_t	s_{t+1}	r_t
0	A	Down	B	2
1	B	Down	B	-4
2	B	Up	B	0
3	B	Up	A	3
4	A	Up	A	-1

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

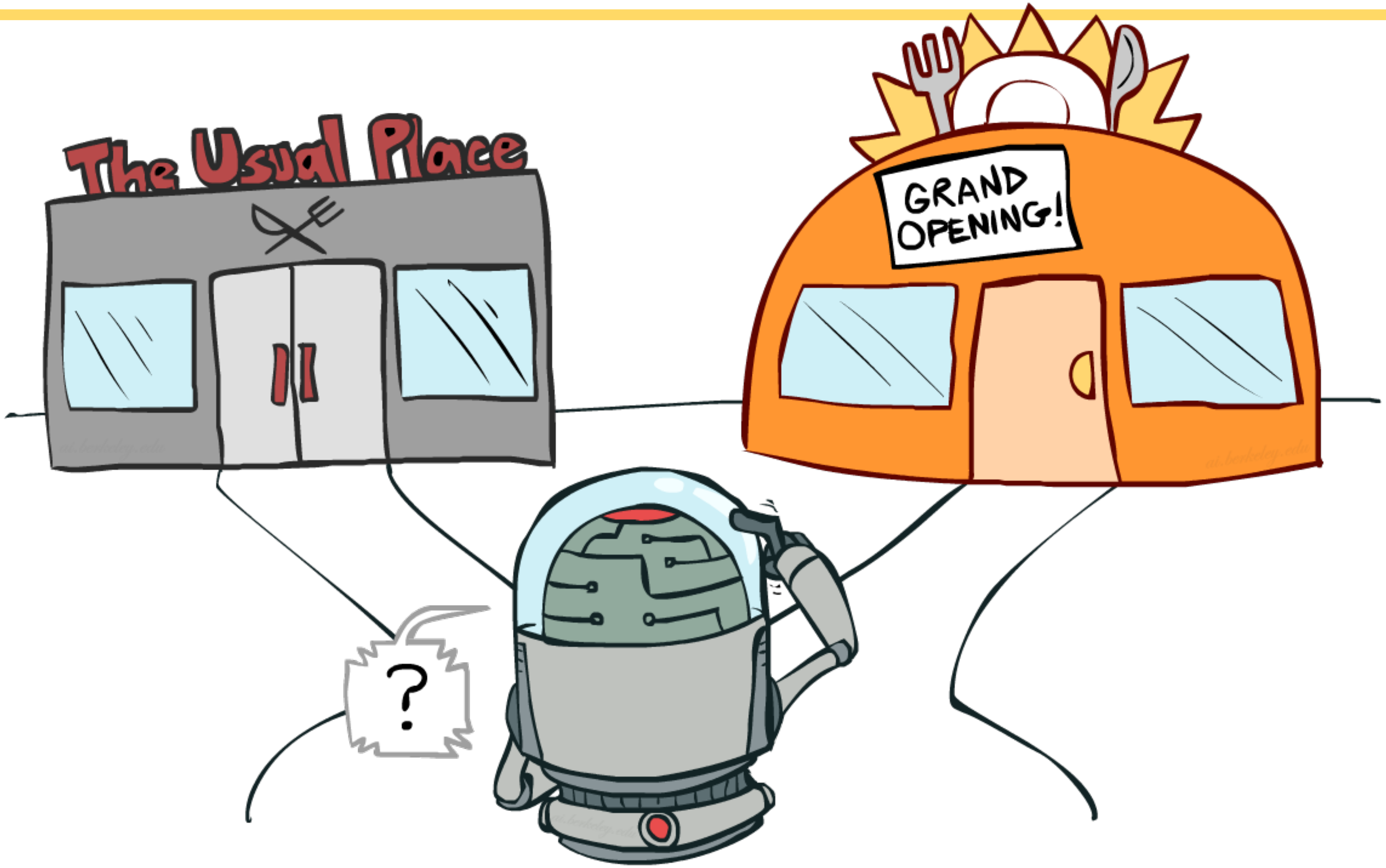
Q-Learning Properties

- Amazing result: Q-learning converges to optimal policy -- even if you're acting suboptimally!

- Caveats:
  - You have to explore enough
  - You have to eventually make the learning rate small enough
  - … but not decrease it too quickly
  - Basically, in the limit, it doesn't matter how you select actions (!)



Exploration vs. Exploitation



How to Explore?

- Several schemes for forcing exploration
  - Simplest: random actions (ε-greedy)
    - Every time step, flip a coin
    - With (small) probability ε, act randomly
    - With (large) probability 1-ε, act on current policy
  - Problems with random actions?
    - You do eventually explore the space, but keep thrashing around once learning is done
    - One solution: lower ε over time
    - Another solution: exploration functions

Exploration Functions

- When to explore?
  - Random actions: explore a fixed amount
  - Better idea: explore areas whose badness is not (yet) established, eventually stop exploring

- Exploration function
  - Takes a value estimate **u** and a visit count n, and returns an optimistic utility, e.g.

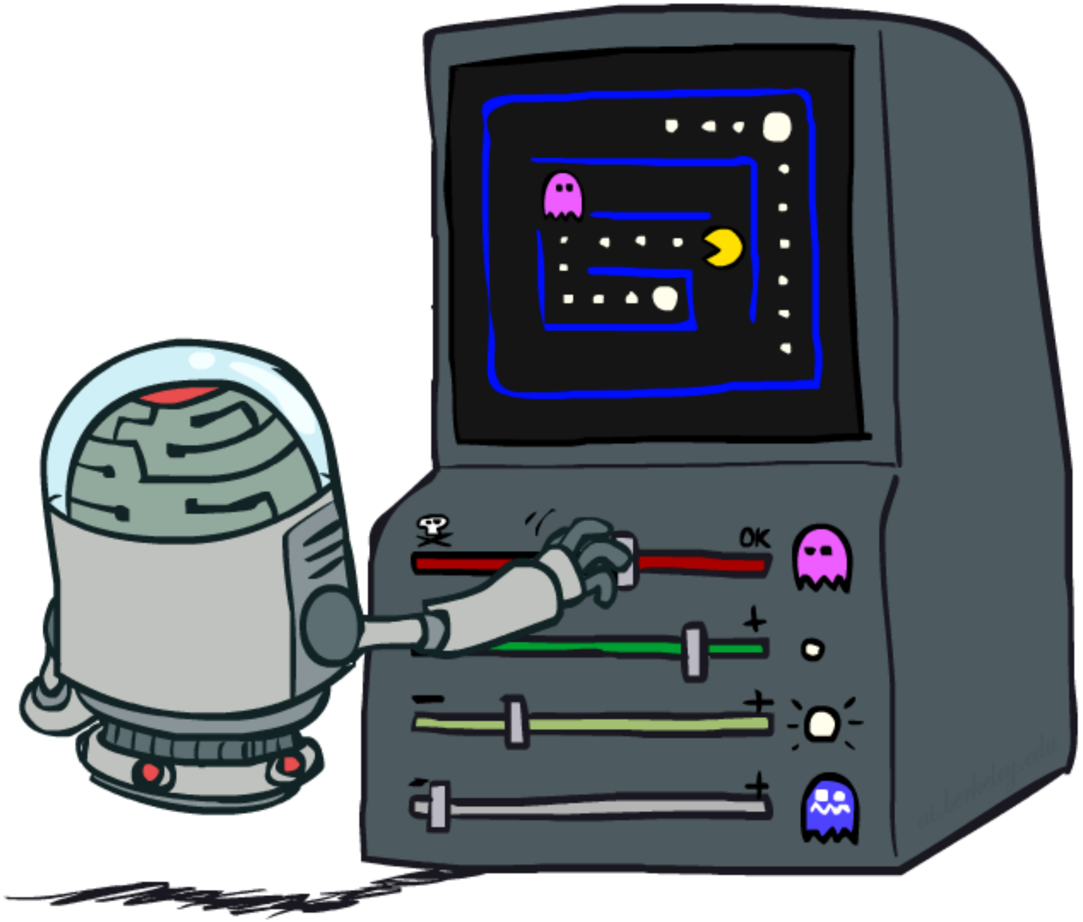
$$f(u,n) = u + k/n$$

Regular Q-Update: $Q(s,a) \leftarrow_\alpha R(s,a,s') + \gamma \max_{a'} Q(s',a')$

Modified Q-Update: $Q(s,a) \leftarrow_\alpha R(s,a,s') + \gamma \max_{a'} f(Q(s',a'), N(s',a'))$

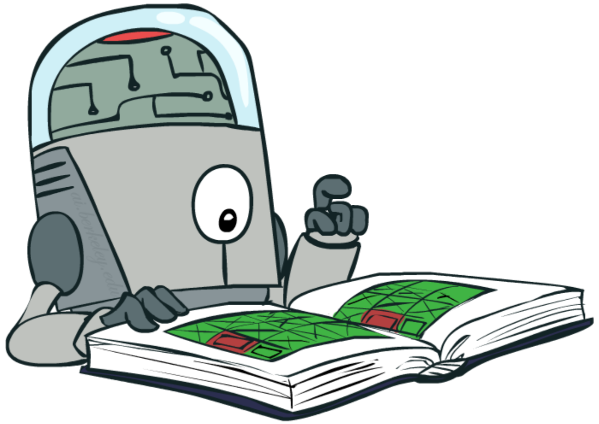
  - Note: this propagates the "bonus" back to states that lead to unknown states as well!

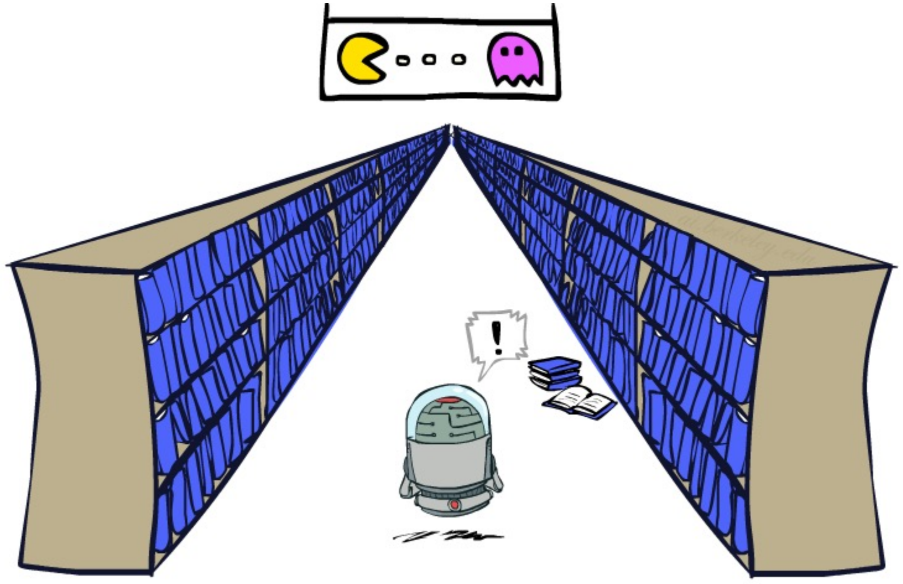
Approximate Q-Learning



Generalizing Across States

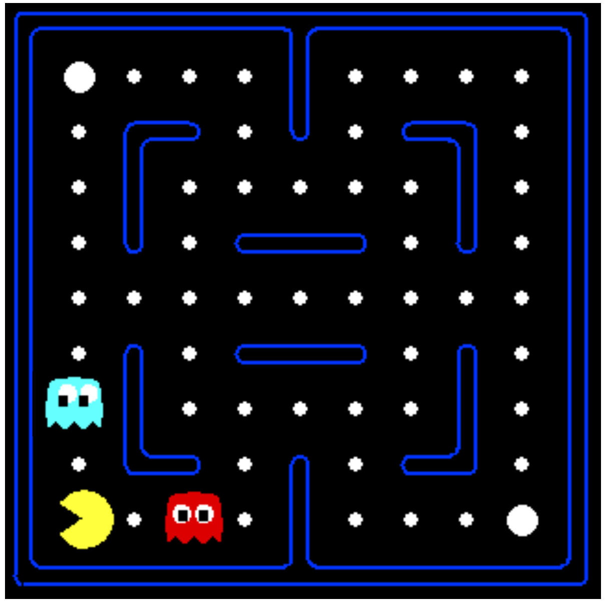
- Basic Q-Learning keeps a table of all q-values
- In realistic situations, we cannot possibly learn about every single state!
  - Too many states to visit them all in training
  - Too many states to hold the q-tables in memory
- Instead, we want to generalize:
  - Learn about some small number of training states from experience
  - Generalize that experience to new, similar situations
  - This is a fundamental idea in machine learning, and we'll see it over and over again



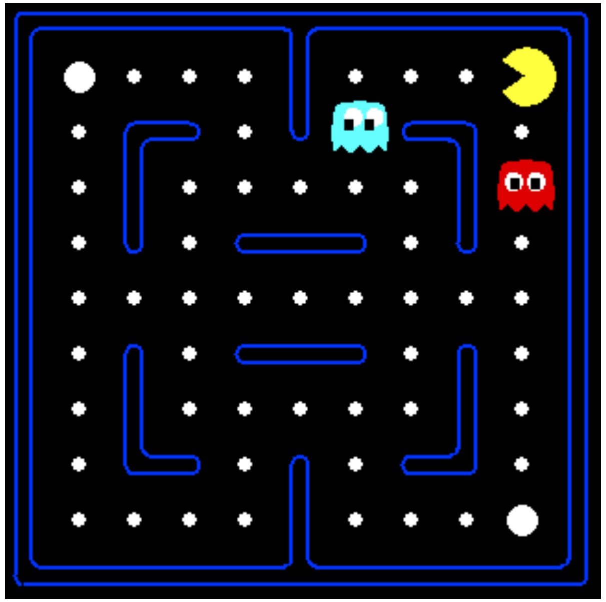


Example: Pacman

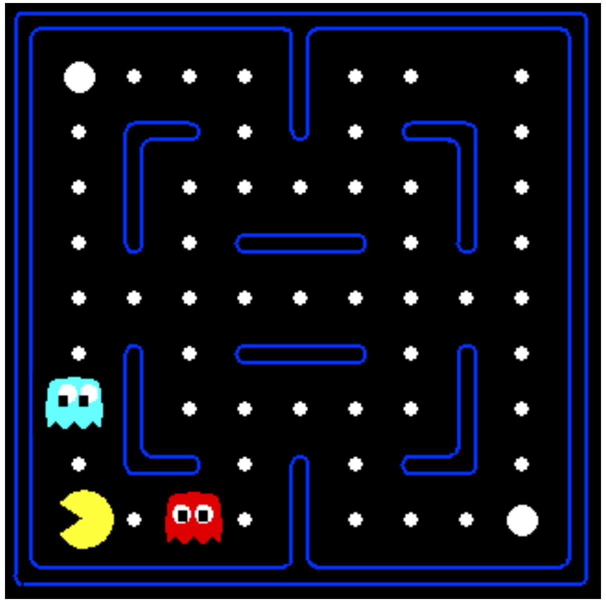
Let's say we discover through experience that this state is bad:



In naïve q-learning, we know nothing about this state:



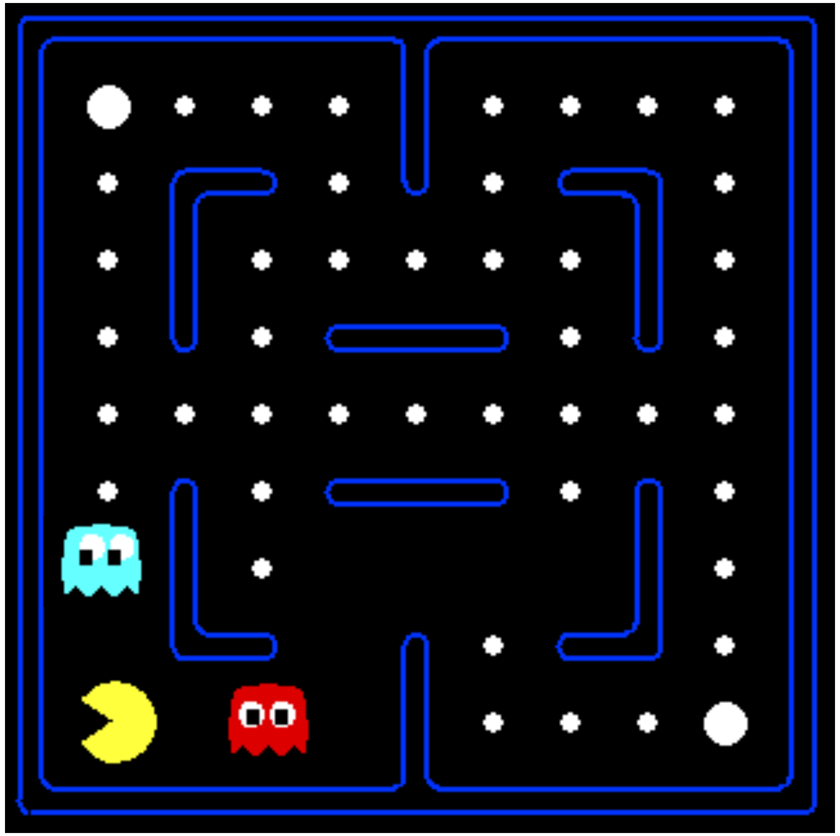
Or even this one!



[Demo: Q-learning – pacman – tiny – watch all (L11D5)],[Demo: Q-learning – pacman – tiny – silent train (L11D6)], [Demo: Q-learning – pacman – tricky – watch all (L11D7)]

Feature-Based Representations

- Solution: describe a state using a vector of features (properties)
  - Features are functions from states to real numbers (often 0/1) that capture important properties of the state
  - Example features:
    - Distance to closest ghost
    - Distance to closest dot
    - Number of ghosts
    - 1 / (dist to dot)^2
    - Is Pacman in a tunnel? (0/1)
    - …… etc.
    - Is it the exact state on this slide?
  - Can also describe a q-state (s, a) with features (e.g. action moves closer to food)



Linear Value Functions

- Using a feature representation, we can write a q function (or value function) for any state using a few weights:

$$V(s) = w_1 f_1(s) + w_2 f_2(s) + \ldots + w_n f_n(s)$$

$$Q(s,a) = w_1 f_1(s,a) + w_2 f_2(s,a) + \ldots + w_n f_n(s,a)$$

- Advantage: our experience is summed up in a few powerful numbers
- Disadvantage: states may share features but actually be very different in value!

Approximate Q-Learning

$$Q(s,a) = w_1 f_1(s,a) + w_2 f_2(s,a) + \ldots + w_n f_n(s,a)$$

- Q-learning with linear Q-functions:

$$\text{transition } = (s, a, r, s')$$

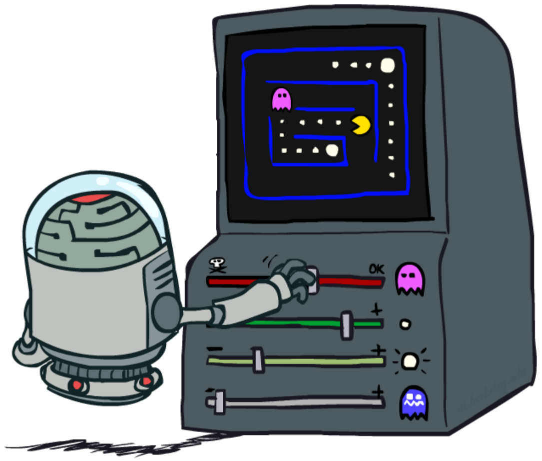
$$\text{difference} = \left[r + \gamma \max_{a'} Q(s', a')\right] - Q(s,a)$$

$$Q(s,a) \leftarrow Q(s,a) + \alpha\,[\text{difference}]$$

Exact Q's

$$w_i \leftarrow w_i + \alpha\,[\text{difference}]\, f_i(s,a)$$

Approximate Q's

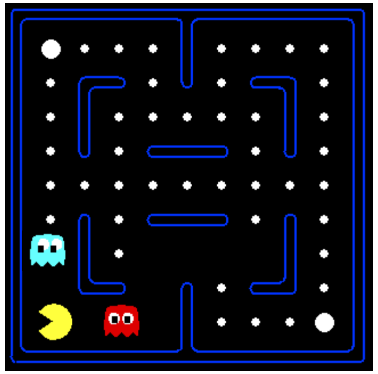


- Intuitive interpretation:
  - Adjust weights of active features
  - E.g., if something unexpectedly bad happens, blame the features that were on: disprefer all states with that state's features
- Formal justification: online least squares

Example: Q-Pacman

$$Q(s,a) = 4.0 f_{DOT}(s,a) - 1.0 f_{GST}(s,a)$$

s

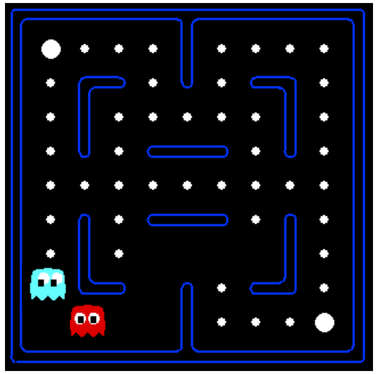


$f_{DOT}(s, \text{NORTH}) = 0.5$

$f_{GST}(s, \text{NORTH}) = 1.0$

$a = \text{NORTH}$
$r = -500$

s'



$Q(s, \text{NORTH}) = +1$

$r + \gamma \max_{a'} Q(s', a') = -500 + 0$

$Q(s', \cdot) = 0$

difference $= -501$

$w_{DOT} \leftarrow 4.0 + \alpha [-501] 0.5$

$w_{GST} \leftarrow -1.0 + \alpha [-501] 1.0$

$$Q(s,a) = 3.0 f_{DOT}(s,a) - 3.0 f_{GST}(s,a)$$

Q-learning with Linear Approximation

Algorithm 4: Q-learning with linear approximation.

Initialize q-value function Q with random weights w: $Q(s,a;w) = \sum_m w_m f_m(s,a)$;
for *episode* $= 1 \rightarrow M$ **do**
    Get initial state s_0;
    for $t = 1 \rightarrow T$ **do**
        With prob. ϵ, select a random action a_t;
        With prob. $1 - \epsilon$, select $a_t \in \operatorname{argmax}_a Q(s_t, a; w)$;
        Execute selected action a_t and observe reward r_t and next state s_{t+1};
        Set target $y_t = \begin{cases} r_t & \text{if episode terminates at step } t+1 \\ r_t + \gamma \max_{a'} Q(s_{t+1}, a'; w) & \text{otherwise} \end{cases}$;
        Perform a gradient descent step to update w: $w_m \leftarrow w_m + \alpha \left[y_t - Q(s_t, a_t; w)\right] f_m(s,a)$;