



**CORE**

Control + Optimization Research Lab

# Deep Deterministic Policy Gradient (DDPG)

이동민

삼성전자 서울대 공동연구소

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# Lecturer

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- 이동민
  - [kid33629@gmail.com](mailto:kid33629@gmail.com)
- 허수빈
  - [62subin.h@gmail.com](mailto:62subin.h@gmail.com)



# Outline

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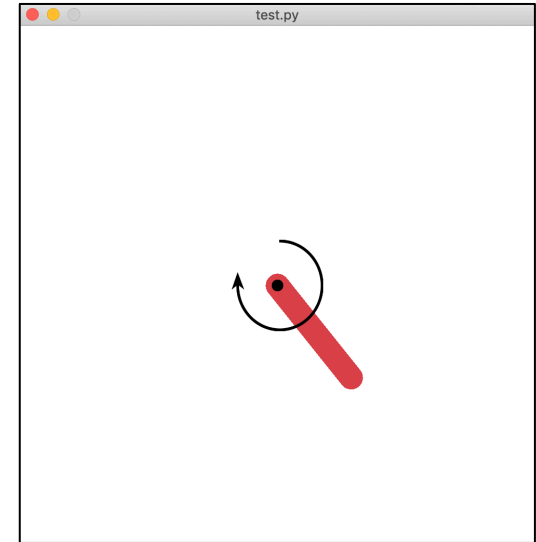
- Environment : Pendulum
- Deep Deterministic Policy Gradient (DDPG)
  - Learning process
  - Hyperparameter
  - Main loop
  - Train model
  - Train & TensorboardX
  - Learning curve & Test
  - DDPG video



# Pendulum

- Env name : Pendulum-v0
- States : Continuous observation spaces

Num	Observation	Min	Max
0	$\cos(\theta)$	-1.0	1.0
1	$\sin(\theta)$	-1.0	1.0
2	$\dot{\theta}$	-8.0	8.0



- Actions : **Continuous** action spaces

Num	Action	Min	Max
0	Joint effort	-2.0	2.0

```
state: [0.88760426 0.46060687 0.60495138] | action: [1.5591747] |  
next_state: [0.8587901 0.5123276 1.18428273] | reward: -0.268161  
02634748273 | done: False  
state: [0.8587901 0.5123276 1.18428273] | action: [1.0582479] |  
next_state: [0.81139809 0.58449392 1.72726561] | reward: -0.430701  
2460303101 | done: False  
state: [0.81139809 0.58449392 1.72726561] | action: [0.7929939] |  
next_state: [0.73948894 0.6731687 2.28458514] | reward: -0.688669  
3000621688 | done: False  
state: [0.73948894 0.6731687 2.28458514] | action: [-0.6580073] |  
next_state: [0.64251266 0.76627507 2.69076057] | reward: -1.06772  
66789916096 | done: False  
state: [0.64251266 0.76627507 2.69076057] | action: [-1.4092577] |  
next_state: [0.51847703 0.85509156 3.05407822] | reward: -1.48817  
52666467798 | done: False
```



# Pendulum

- Reward

The precise equation for reward:

$$-(\theta^2 + 0.1 \cdot \dot{\theta}^2 + 0.001 \cdot a^2)$$

Theta is normalized between  $-\pi$  and  $\pi$ . Therefore, the lowest cost is  $-(\pi^2 + 0.1 \cdot 8^2 + 0.001 \cdot 2^2) = -16.2736044$ , and the highest cost is  $0$ . In essence, the goal is to remain at zero angle (vertical), with the least rotational velocity, and the least effort.

- Episode Termination

There is no specified termination. Adding a maximum number of steps might be a good idea.

NOTE: Your environment object could be wrapped by the TimeLimit wrapper, if created using the "gym.make" method. In that case it will terminate after 200 steps.

# Deep Deterministic Policy Gradient (DDPG)

- DDPG Algorithm

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**Algorithm 1** DDPG algorithm

---

Randomly initialize critic network  $Q(s, a|\theta^Q)$  and actor  $\mu(s|\theta^\mu)$  with weights  $\theta^Q$  and  $\theta^\mu$ .

Initialize target network  $Q'$  and  $\mu'$  with weights  $\theta^{Q'} \leftarrow \theta^Q, \theta^{\mu'} \leftarrow \theta^\mu$

Initialize replay buffer  $R$

**for** episode = 1, M **do**

    Initialize a random process  $\mathcal{N}$  for action exploration

    Receive initial observation state  $s_1$

**for** t = 1, T **do**

        Select action  $a_t = \mu(s_t|\theta^\mu) + \mathcal{N}_t$  according to the current policy and exploration noise

        Execute action  $a_t$  and observe reward  $r_t$  and observe new state  $s_{t+1}$

        Store transition  $(s_t, a_t, r_t, s_{t+1})$  in  $R$

        Sample a random minibatch of  $N$  transitions  $(s_i, a_i, r_i, s_{i+1})$  from  $R$

        Set  $y_i = r_i + \gamma Q'(s_{i+1}, \mu'(s_{i+1}|\theta^{\mu'})|\theta^{Q'})$

        Update critic by minimizing the loss:  $L = \frac{1}{N} \sum_i (y_i - Q(s_i, a_i|\theta^Q))^2$

        Update the actor policy using the sampled policy gradient:

$$\nabla_{\theta^\mu} J \approx \frac{1}{N} \sum_i \nabla_a Q(s, a|\theta^Q)|_{s=s_i, a=\mu(s_i)} \nabla_{\theta^\mu} \mu(s|\theta^\mu)|_{s_i}$$

    Update the target networks:

$$\theta^{Q'} \leftarrow \tau \theta^Q + (1 - \tau) \theta^{Q'}$$

$$\theta^{\mu'} \leftarrow \tau \theta^\mu + (1 - \tau) \theta^{\mu'}$$

**end for**

**end for**

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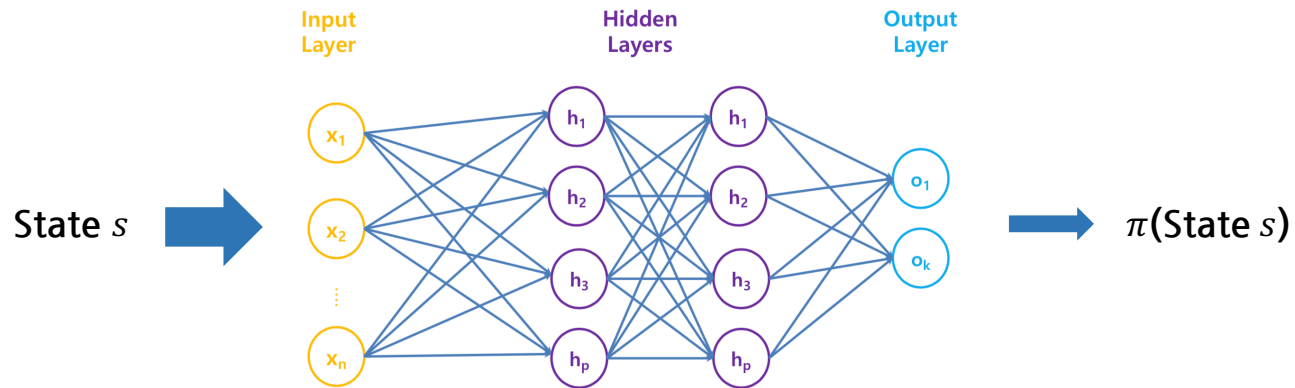
# Deep Deterministic Policy Gradient (DDPG)

- Learning process
  1. 상태에 따른 행동 선택
  2. 환경에서 선택한 행동으로 한 time step을 진행한 후, 다음 상태와 보상을 받음
  3. Sample  $(s, a, r, s')$ 을 replay buffer에 저장
  4. Replay buffer에서 랜덤으로 sample을 추출
  5. 추출한 sample로 Actor & Critic network 업데이트
  6. Actor & Critic에 대해 Soft target 업데이트

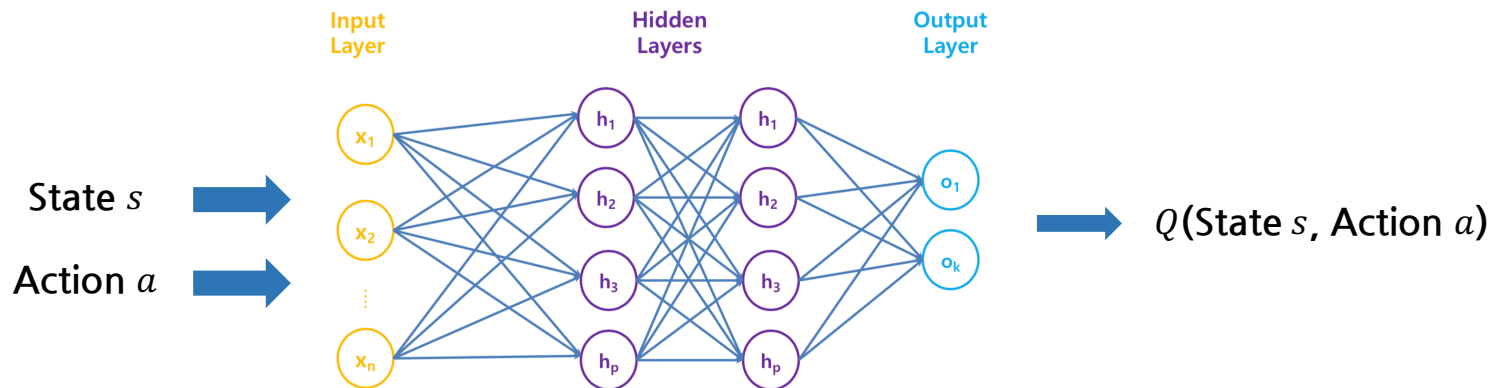


# Deep Deterministic Policy Gradient (DDPG)

- Actor network



- Critic network





# Deep Deterministic Policy Gradient (DDPG)

- Actor network

```
4  class Actor(nn.Module):
5      def __init__(self, state_size, action_size, args):
6          super(Actor, self).__init__()
7          self.fc1 = nn.Linear(state_size, args.hidden_size)
8          self.fc2 = nn.Linear(args.hidden_size, args.hidden_size)
9          self.fc3 = nn.Linear(args.hidden_size, action_size)
10
11     def forward(self, x):
12         x = torch.relu(self.fc1(x))
13         x = torch.relu(self.fc2(x))
14         policy = self.fc3(x)
15
16         return policy
```



# Deep Deterministic Policy Gradient (DDPG)

- Critic network

```
18 class Critic(nn.Module):
19     def __init__(self, state_size, action_size, args):
20         super(Critic, self).__init__()
21         self.fc1 = nn.Linear(state_size + action_size, args.hidden_size)
22         self.fc2 = nn.Linear(args.hidden_size, args.hidden_size)
23         self.fc3 = nn.Linear(args.hidden_size, 1)
24
25     def forward(self, states, actions):
26         x = torch.cat([states, actions], dim=1)
27         x = torch.relu(self.fc1(x))
28         x = torch.relu(self.fc2(x))
29         q_value = self.fc3(x)
30
31         return q_value
```



# Learning process

## 1. 상태에 따른 행동 선택

```
114 policy = actor(torch.Tensor(state))
115 action = get_action(policy, ou_noise) train.py
```

```
19 def get_action(policy, ou_noise):
20     action = policy.detach().numpy() + ou_noise.sample()
21
22     return action utils.py
```

- Ornstein-Uhlenbeck noise (OU noise) - theta : 0.15, mu : 0.0, sigma : 0.2
  - $dx_t = \theta(\mu - x_t)dt + \sigma dW_t$

```
4 class OUNoise:
5     def __init__(self, action_size, theta, mu, sigma):
6         self.action_size = action_size
7         self.theta = theta
8         self.mu = mu
9         self.sigma = sigma
10        self.X = np.zeros(self.action_size)
11
12        def sample(self):
13            dx = self.theta * (self.mu - self.X)
14            dx = dx + self.sigma * np.random.randn(len(self.X))
15            self.X = self.X + dx
16
17            return self.X
```

```
dx [-0.25447483]
X [-0.25447483]

dx [-0.20936269]
X [-0.46383752]

dx [0.1268112]
X [-0.33702632]

dx [0.18123875]
X [-0.15578757]

dx [-0.0240699]
X [-0.17985747]
```

utils.py



# Learning process

2. 환경에서 선택한 행동으로 한 time step을 진행한 후, 다음 상태와 보상을 받음

```
117         next_state, reward, done, _ = env.step(action)
```

3. Sample  $(s, a, r, s')$ 을 replay buffer에 저장

```
97         replay_buffer = deque(maxlen=10000)
```

```
120         mask = 0 if done else 1
```

```
121
```

```
122         replay_buffer.append((state, action, reward, next_state, mask))
```

4. Replay buffer에서 랜덤으로 sample을 추출 (Batch size : 64)

```
128         mini_batch = random.sample(replay_buffer, args.batch_size)
```



# Learning process

## 5. 추출한 sample로 Actor & Critic network 업데이트

- Critic Loss

$$J_Q(\phi) = ( \underbrace{r + \gamma Q_{\phi}(s', \pi_{\theta}(s'))}_{\text{Target}} - \underbrace{Q_{\phi}(s, a)}_{\text{Prediction}} )^2$$

```
49 # update critic
50 criterion = torch.nn.MSELoss()
51
52 # get Q-value
53 q_value = critic(torch.Tensor(states), actions).squeeze(1)
54
55 # get target
56 target_next_policy = target_actor(torch.Tensor(next_states))
57 target_next_q_value = target_critic(torch.Tensor(next_states), target_next_policy).squeeze(1)
58 target = rewards + masks * args.gamma * target_next_q_value
59
60 critic_loss = criterion(q_value, target.detach())
61 critic_optimizer.zero_grad()
62 critic_loss.backward()
63 critic_optimizer.step()
```



# Learning process

## 5. 추출한 sample로 Actor & Critic network 업데이트

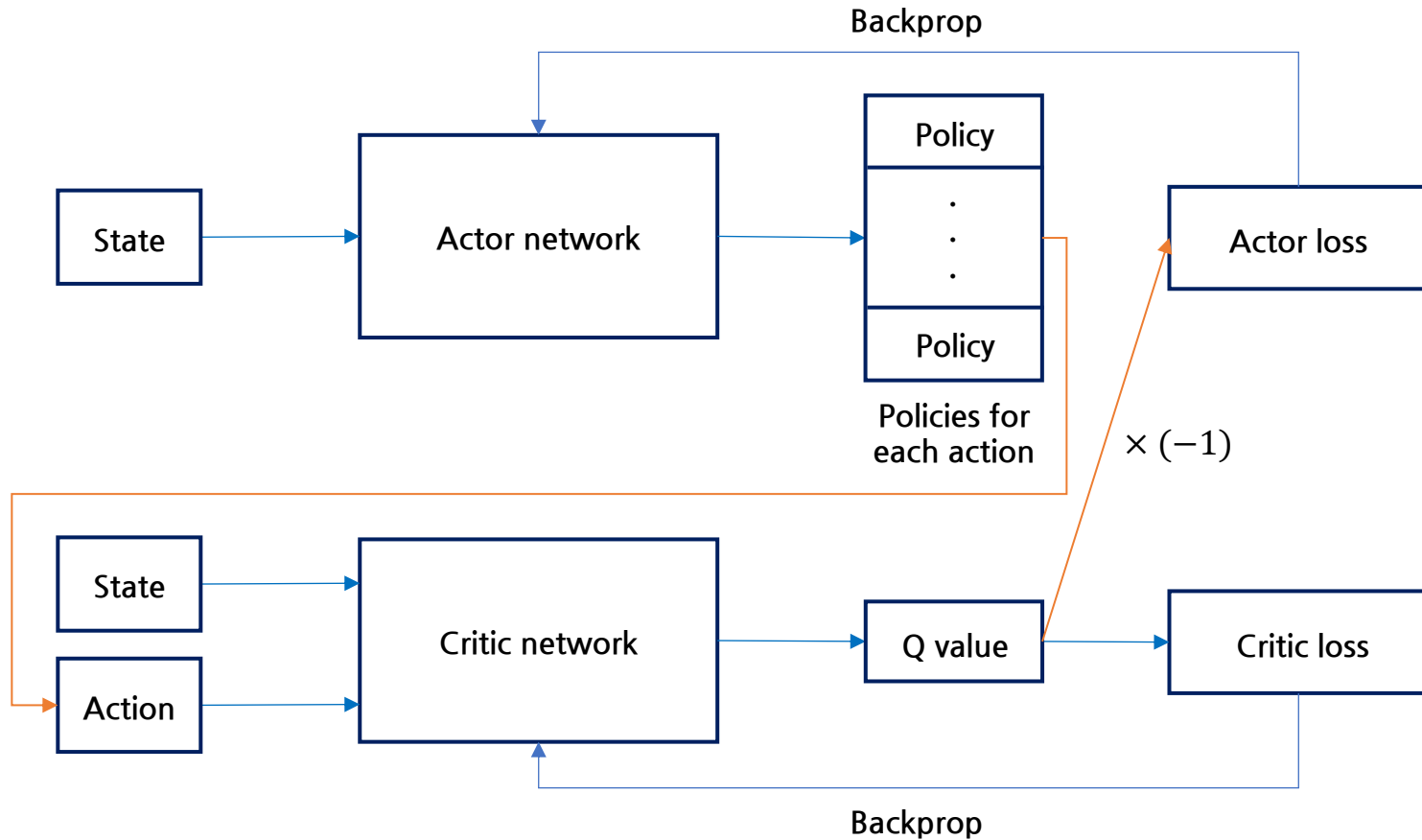
- Actor Loss

$$J_{\pi}(\theta) = -\frac{1}{N} \sum Q_{\phi}(s, \pi_{\theta}(s))$$

```
65     # update actor
66     policy = actor(torch.Tensor(states))
67
68     actor_loss = -critic(torch.Tensor(states), policy).mean()
69     actor_optimizer.zero_grad()
70     actor_loss.backward()
71     actor_optimizer.step()
```



# Learning process



# Learning process

## 6. Actor & Critic에 대해 Soft target 업데이트

- Initialize target model

```
92     hard_target_update(actor, critic, target_actor, target_critic) train.py
```

```
24 def hard_target_update(actor, critic, target_actor, target_critic):  
25     target_critic.load_state_dict(critic.state_dict())  
26     target_actor.load_state_dict(actor.state_dict()) utils.py
```

- Soft target update ( $\tau : 0.001$ )

$$\phi^{Q'} \leftarrow \tau \phi^Q + (1 - \tau) \phi^{Q'}$$

$$\theta^{\pi'} \leftarrow \tau \theta^{\pi} + (1 - \tau) \theta^{\pi'}$$

train.py

```
135     soft_target_update(actor, critic, target_actor, target_critic, args.tau)
```

```
28 def soft_target_update(actor, critic, target_actor, target_critic, tau):  
29     soft_update(critic, target_critic, tau)  
30     soft_update(actor, target_actor, tau)  
31  
32 def soft_update(net, target_net, tau):  
33     for param, target_param in zip(net.parameters(), target_net.parameters()):  
34         target_param.data.copy_(tau * param.data + (1.0 - tau) * target_param.data) utils.py
```





# Hyperparameter

```
15 parser = argparse.ArgumentParser()
16 parser.add_argument('--env_name', type=str, default="Pendulum-v0")
17 parser.add_argument('--load_model', type=str, default=None)
18 parser.add_argument('--save_path', default='./save_model/', help='')
19 parser.add_argument('--render', action="store_true", default=False)
20 parser.add_argument('--gamma', type=float, default=0.99)
21 parser.add_argument('--hidden_size', type=int, default=64)
22 parser.add_argument('--batch_size', type=int, default=64)
23 parser.add_argument('--actor_lr', type=float, default=1e-3)
24 parser.add_argument('--critic_lr', type=float, default=1e-3)
25 parser.add_argument('--theta', type=float, default=0.15)
26 parser.add_argument('--mu', type=float, default=0.0)
27 parser.add_argument('--sigma', type=float, default=0.2)
28 parser.add_argument('--tau', type=float, default=0.001)
29 parser.add_argument('--max_iter_num', type=int, default=1000)
30 parser.add_argument('--log_interval', type=int, default=10)
31 parser.add_argument('--goal_score', type=int, default=-300)
32 parser.add_argument('--logdir', type=str, default='./logs',
33 | | | | | help='tensorboardx logs directory')
34 args = parser.parse_args()
```



# Main loop

- Initialization
  - Seed - random number 고정
  - Actor & Critic network
  - Target actor & critic network
  - Actor & Critic optimizer
  - Hard target update
  - OU noise
  - TensorboardX
  - Replay buffer
  - Recent rewards

```
74 def main():
75     env = gym.make(args.env_name)
76     env.seed(500)
77     torch.manual_seed(500)
78
79     state_size = env.observation_space.shape[0]
80     action_size = env.action_space.shape[0]
81     print('state size:', state_size)
82     print('action size:', action_size)
83
84     actor = Actor(state_size, action_size, args)
85     target_actor = Actor(state_size, action_size, args)
86     critic = Critic(state_size, action_size, args)
87     target_critic = Critic(state_size, action_size, args)
88
89     actor_optimizer = optim.Adam(actor.parameters(), lr=args.actor_lr)
90     critic_optimizer = optim.Adam(critic.parameters(), lr=args.critic_lr)
91
92     hard_target_update(actor, critic, target_actor, target_critic)
93     ou_noise = OUNoise(action_size, args.theta, args.mu, args.sigma)
94
95     writer = SummaryWriter(args.logdir)
96
97     replay_buffer = deque(maxlen=10000)
98     recent_rewards = deque(maxlen=100)
99     steps = 0
```



# Main loop

- Episode 진행
  - 상태에 따른 행동 선택
  - 다음 상태와 보상을 받음
  - Replay buffer에 저장

```
101 for episode in range(args.max_iter_num):
102     done = False
103     score = 0
104
105     state = env.reset()
106     state = np.reshape(state, [1, state_size])
107
108     while not done:
109         if args.render:
110             env.render()
111
112         steps += 1
113
114         policy = actor(torch.Tensor(state))
115         action = get_action(policy, ou_noise)
116
117         next_state, reward, done, _ = env.step(action)
118
119         next_state = np.reshape(next_state, [1, state_size])
120         mask = 0 if done else 1
121
122         replay_buffer.append((state, action, reward, next_state, mask))
123
124         state = next_state
125         score += reward
```



# Main loop

- Episode 진행
  - Replay buffer에서 랜덤으로 64개의 sample을 추출 → Mini batch
  - Train model
  - Soft target update

```
127         if steps > args.batch_size:
128             mini_batch = random.sample(replay_buffer, args.batch_size)
129
130             actor.train(), critic.train()
131             target_actor.train(), target_critic.train()
132             train_model(actor, critic, target_actor, target_critic,
133                         actor_optimizer, critic_optimizer, mini_batch)
134
135             soft_target_update(actor, critic, target_actor, target_critic, args.tau)
136
137         if done:
138             recent_rewards.append(score)
```

# Main loop

- Print & Visualize log
- Termination : 최근 100개의 episode의 평균 score가 -300보다 크다면
  - Save model
  - 학습 종료

```
140         if episode % args.log_interval == 0:
141             print('{} episode | score_avg: {:.2f}'.format(episode, np.mean(recent_rewards)))
142             writer.add_scalar('log/score', float(score), episode)
143
144         if np.mean(recent_rewards) > args.goal_score:
145             if not os.path.isdir(args.save_path):
146                 os.makedirs(args.save_path)
147
148             ckpt_path = args.save_path + 'model.pth'
149             torch.save(actor.state_dict(), ckpt_path)
150             print('Recent rewards exceed -300. So end')
151             break
```

# Train model

- Mini batch → Numpy array
- Mini batch에 있는 64개의 sample들을 각각 나눔
  - state - (64, 3)
  - action - (64, 1)
  - reward - (64)
  - next\_state - (64, 3)
  - mask - (64)

```
36 def train_model(actor, critic, target_actor, target_critic,
37                 actor_optimizer, critic_optimizer, mini_batch):
38     mini_batch = np.array(mini_batch)
39     states = np.vstack(mini_batch[:, 0])
40     actions = list(mini_batch[:, 1])
41     rewards = list(mini_batch[:, 2])
42     next_states = np.vstack(mini_batch[:, 3])
43     masks = list(mini_batch[:, 4])
44
45     actions = torch.Tensor(actions).squeeze(1)
46     rewards = torch.Tensor(rewards).squeeze(1)
47     masks = torch.Tensor(masks)
```



# Train model

- Prediction
  - q\_value - (64)
- Target
  - target\_next\_policy - (64, 1)
  - target\_next\_q\_value - (64)
  - target - (64)
- Update critic - MSE Loss
  - $J_Q(\phi) = (r + \gamma Q_\phi(s', \pi_\theta(s')) - Q_\phi(s, a))^2$

```
49     # update critic
50     criterion = torch.nn.MSELoss()
51
52     # get Q-value
53     q_value = critic(torch.Tensor(states), actions).squeeze(1)
54
55     # get target
56     target_next_policy = target_actor(torch.Tensor(next_states))
57     target_next_q_value = target_critic(torch.Tensor(next_states), target_next_policy).squeeze(1)
58     target = rewards + masks * args.gamma * target_next_q_value
59
60     critic_loss = criterion(q_value, target.detach())
61     critic_optimizer.zero_grad()
62     critic_loss.backward()
63     critic_optimizer.step()
```



# Train model

- Update actor
  - policy - (64, 1)
  - `critic(torch.Tensor(state), policy)` - (64, 1)
  - $J_{\pi}(\theta) = -\frac{1}{N} \sum Q_{\phi}(s, \pi_{\theta}(s))$

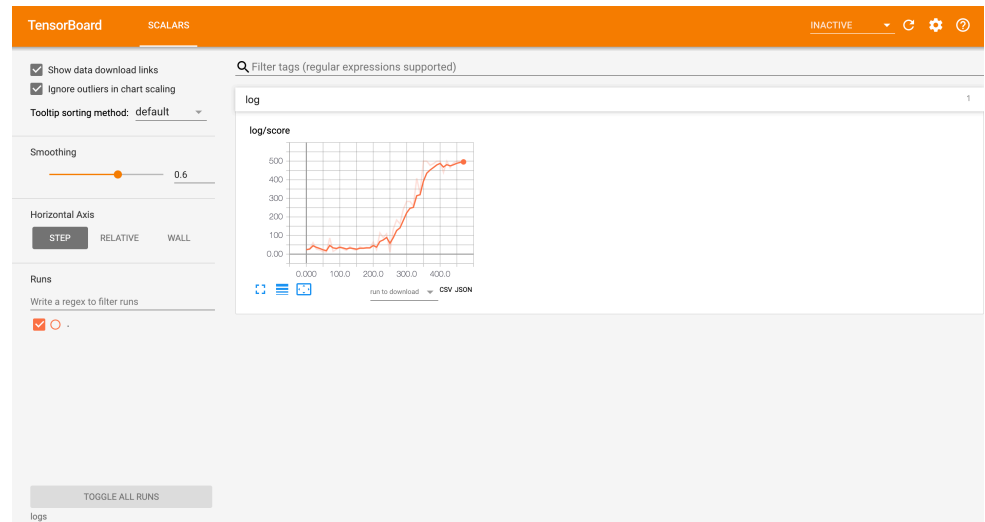
```
65     # update actor
66     policy = actor(torch.Tensor(states))
67
68     actor_loss = -critic(torch.Tensor(states), policy).mean()
69     actor_optimizer.zero_grad()
70     actor_loss.backward()
71     actor_optimizer.step()
```





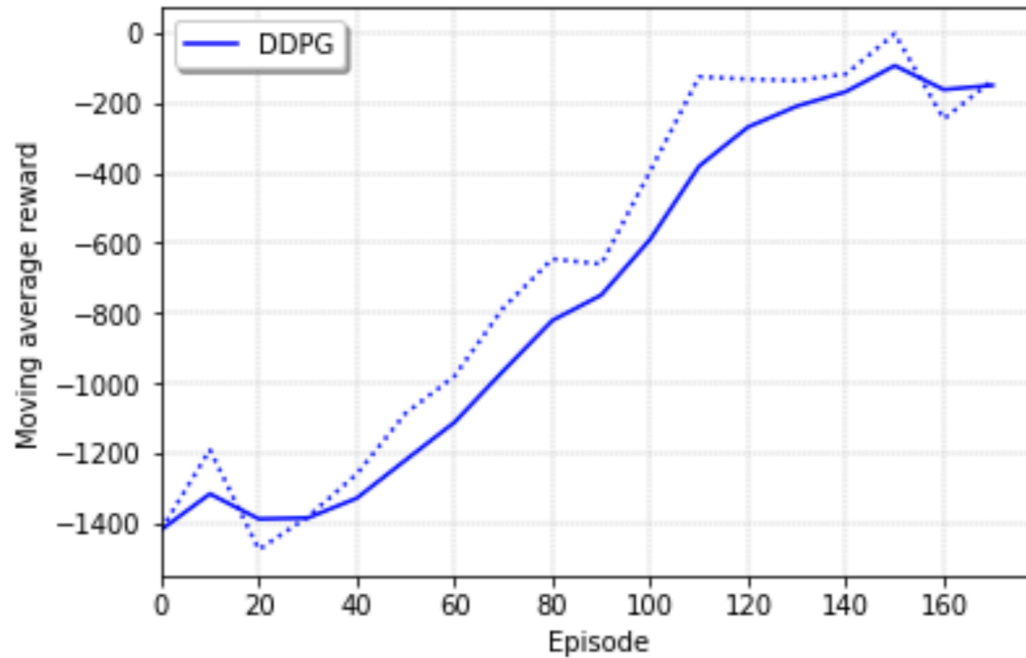
# Train & TensorboardX

- Terminal A - train 실행
  - `conda activate env_name`
  - `python train.py`
- Terminal B - tensorboardX 실행
  - `conda activate env_name`
  - `tensorboard --logdir logs`
  - (웹에서) `localhost:6006`



# Learning curve & Test

- Learning curve



- Test
  - `python test.py`

# DDPG video

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- Learning to move: DDPG Algorithms on Gym MuJoCo  
<https://www.youtube.com/watch?v=iFg5lcUzSYU&t=14>
- Deep RL for Robotic Manipulation (DDPG + HER)  
<https://www.youtube.com/watch?v=K-foX756KTc&t=44>



Thank you

