

# CSC3022F Machine Learning Assignment 2

*Scenario 1: Exploration Strategy Analysis*

*Reinforcement Learning - Four Rooms Domain*

## Exploration Strategy Comparison

Two distinct exploration strategies were implemented and compared for Q-learning in the Four Rooms environment:

Strategy	Initial $\epsilon$	Decay Rate	Min $\epsilon$	Characteristics
<b>High Exploration</b>	1.0	0.995	0.01	Aggressive exploration with slow decay
<b>Moderate Exploration</b>	0.5	0.99	0.01	Balanced approach with faster decay

## Key Experimental Findings

**Learning Speed:** High exploration demonstrates slower initial convergence due to extensive random action selection, but achieves superior long-term stability. Moderate exploration converges more rapidly in early episodes but exhibits higher variance and potential for suboptimal policy convergence.

**Final Policy Quality:** Both strategies ultimately achieve optimal performance metrics (average reward  $\approx 0.96$ , average steps  $\approx 5$ ) in the single-package collection task, demonstrating that sufficient exploration eventually leads to equivalent optimal policies in this environment.

**Stability Across Runs:** High exploration exhibits significantly greater stability and consistency across multiple training runs, producing smoother learning curves with reduced variance. The moderate exploration strategy shows higher sensitivity to initialization and may require multiple runs to achieve consistent performance.

## Technical Implementation Analysis

The Q-learning implementation utilizes exponential epsilon decay with  $\epsilon$ -greedy action selection. The state space encoding efficiently captures agent position (x,y) and remaining packages, while the reward structure (+1 for package collection, -0.01 for movement) provides appropriate incentive alignment for optimal path-finding behavior.

**Conclusion:** While both exploration strategies achieve optimal performance in this relatively simple domain, the high exploration approach demonstrates superior robustness and training stability. The generated learning curve visualizations clearly illustrate these behavioral differences, with high exploration producing more reliable convergence patterns despite requiring additional training episodes for initial policy refinement.

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