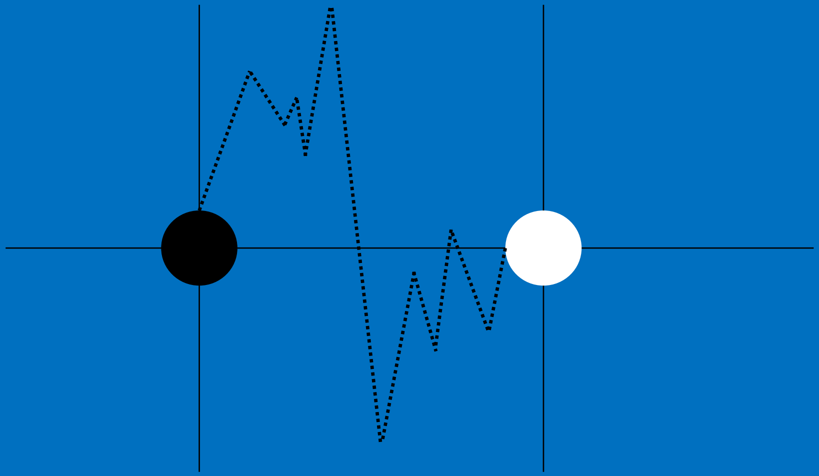
From AlphaGo to AlphaZero

1. Mastering the Game of Go with Deep Neural Networks and Tree Search (2016)
2. Mastering the Game of Go without Human Knowledge (2017)
3. Mastering Chess and Shogi by Self-Play with a General Reinforcement Learning Algorithm (2017)



- By Shijie Huang (Harvey)

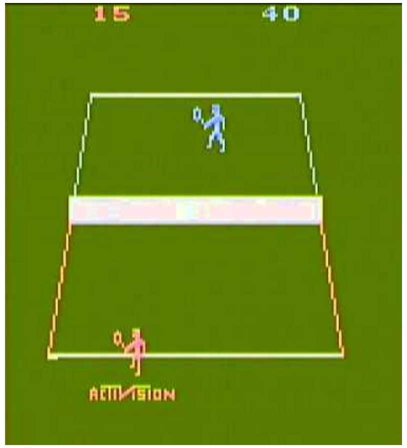
- 11 December 2017

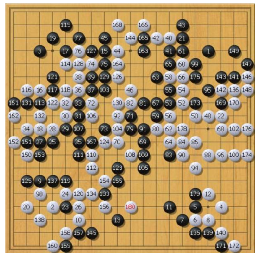
Content

- Deep Reinforcement Learning in Different Games
- Go Game: Basic Rules
- AlphaGo
  - Why Go and Prior Work
  - Structure Breakdown
  - Supervised Learning of Policy Networks
  - Policy and Policy Networks
  - Reinforcement Learning: Policy Networks
  - Reinforcement Learning: Value Networks and Position Evaluation
  - Monte Carlo Tree Search: Search with Policy and Value Networks
- AlphaGo Zero
  - Deep Neural Network – Structure Breakdown
  - Monte Carlo Tree Search: Search with a Single Neural Network
- Humans, AlphaGo and AlphaGo Zero
- Discussions
- AlphaZero

1. Deep Reinforcement Learning in Different Games

Assumption: AI can only see/do what humans can see/do



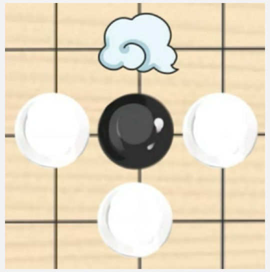


Games	Atari	Board Game	Dota / LOL	Starcraft II
Agents	1	2	≥ 1 (Generally 5 vs. 5)	≥ 2 (Generally 1 vs. 1)
Information	Perfect information	Perfect Information	Imperfect information (fog of war)	Imperfect information (fog of war)
State space	Limited	Limited but large	Unlimited	Unlimited
Action space	Limited	Limited but large	Limited but large	Unlimited
AI vs. Human	AI dominated	AI dominated	AI won in 1 vs. 1 Completely failed in 5 vs. 5 (OpenAI)	Completely failed in any competitive game but learn to do simple tasks (DeepMind)

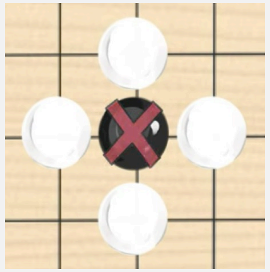
1. Go Game: Basic Rules

How to play

Liberty

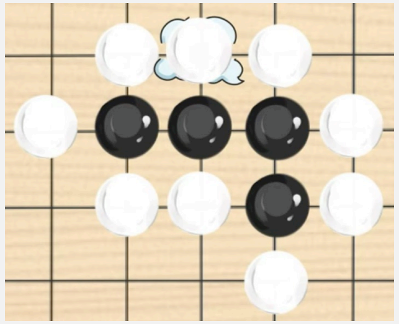


- Liberty is when the area surrounding the go has no other go



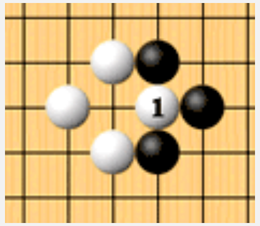
- If a go has no liberty, it is consider ”dead” and will be taken out

Liberty (Multiple Go)



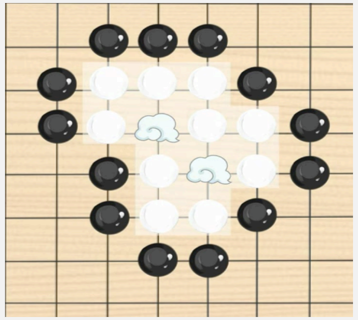
- In this case, black gos are “dead” and will be taken out

Ko Rule



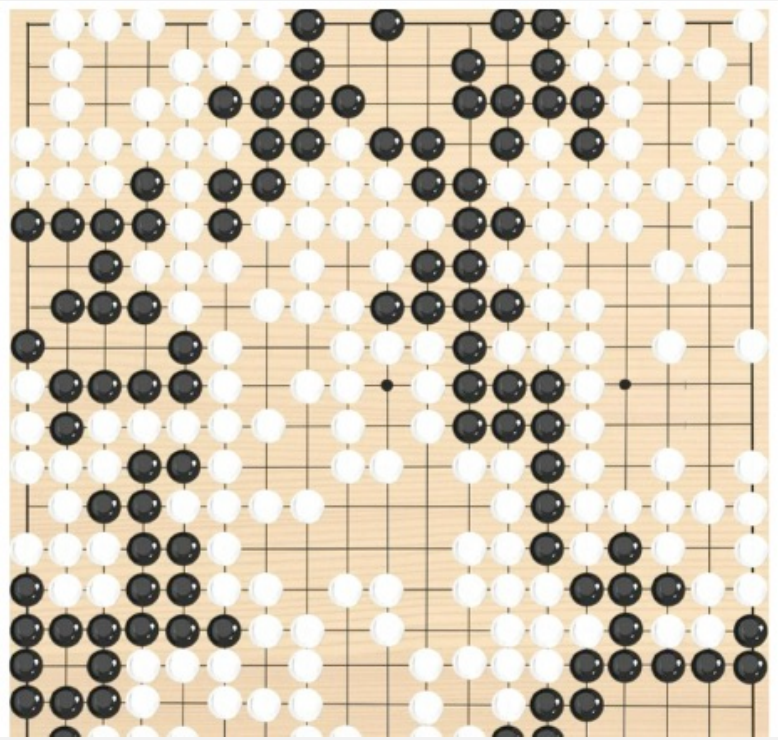
- One cannot place the go in “dead” area
- Essence of many strategies
- Note that it appears that old version of AlphaGo made mistakes here

Life



- If go is surrounded but the “Ko” rule applies, then this area of go is considered to be “alive” (life)
- In the case shown in the left, black gos cannot be placed inside the white gos. Hence, white gos are considered to be “alive”

How to win



The winner is:

1. whoever occupies more areas of the board
2. whoever has more number of go on the board
3. rules are country dependent but only minor differences exist

AlphaGo

An “interesting” fact about AlphaGo:
The most powerful version consists of 1920 CPUs and 280 GPUs
Electricity bill is \$3000 per game, training phase: 160,000 game $\approx$ \$480 million

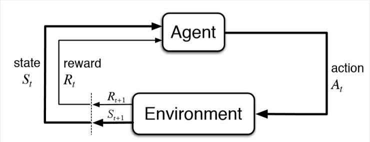
2. Why Go and Prior Work

Why Go Game?

- Most challenging of classic games in computer science
- 19 X 19 board positions
- 250^{150} possible sequences of moves (chess: 35^{80})
- The idea of broad picture: the objective is to occupy more territory.
  - Leads to highly sophisticated evaluation functions
  - No one before AlphaGo has successfully build an effective evaluation function
- Exhaustive search is infeasible.
- Still within the scope of perfect information

Prior Work

Reinforcement Learning



Self-play

Linear Value Function

$$V_\theta(s) = \phi(s)^T\theta$$

Tree Search

Minimax (Alpha-Beta) Tree Search

- Most game too large for Minimax Tree Search because it requires one to go all the way to the end of the game
- Truncate the tree by using approximated value function $V_\theta(s) \approx v^*(s)$
- Super-human performance in chess
- Not effective in Go

Monte Carlo Tree Search

- Double approximation
- $V^n(s) \approx v^{p_n}(s) \approx v^*(s)$
- First use Monte Carlo simulations to estimate the value function of a policy p^n
- Second use the value function to approximate the optimal value function
- Why does it work? In the limit they are equivalent

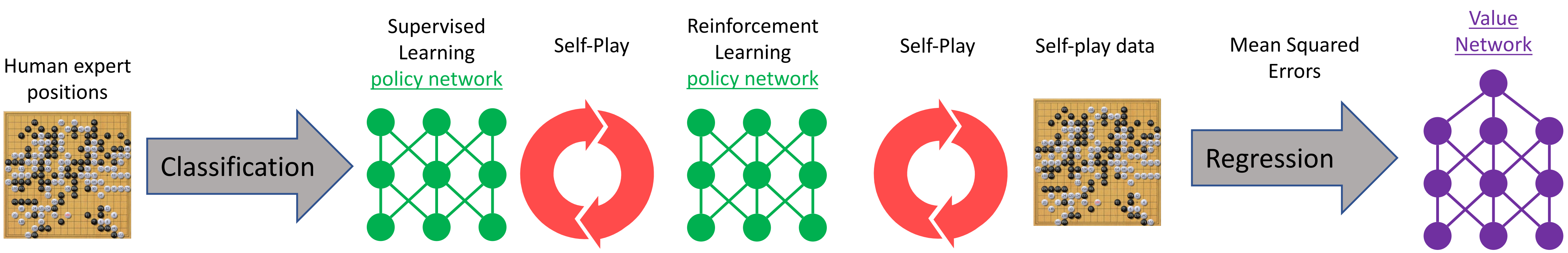
Why?

Reinforcement Learning: Neurobiology foundations

Tree Search: Players tend to make forecasts (truncated) and predictions

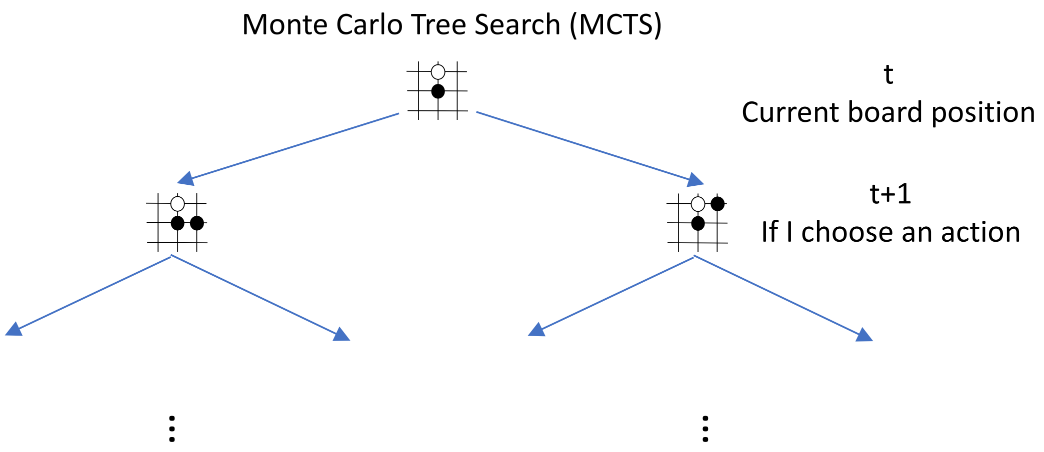
2. AlphaGo: Structure Breakdown

Training Pipeline



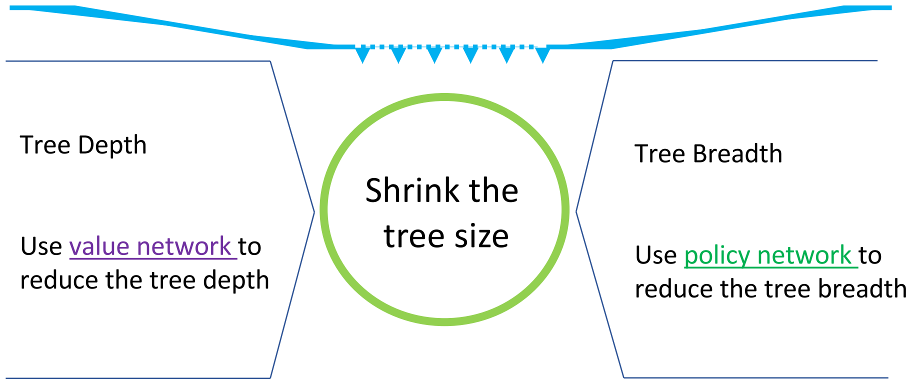
(Silver et al. 2016)

Testing/Tournament



(Silver et al. 2016)

Problems with pure MCTS
• Tree depth: need to simulate all the way to the end of the game
• Tree breadth: enormous amount of choices per time step



2. AlphaGo: Supervised Learning of Policy Networks

Convolutional Neural Network

CNN Training and Testing

- To predict human experts move
- 160,000 games (professional players)
- 29.4 Million moves (28.4 million training and 1 million testing)
- Stochastic Gradient Descent update to maximize the action log likelihood

Prediction accuracy: 55-57%

If I feed the neural network with a board status (state), the neural network can predict, on average 55-57% chance, the correct move that a human expert will do under the same board condition

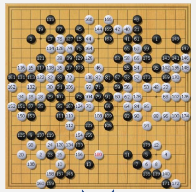
Better accuracy or higher chances of winning?
After all, human (including experts) make mistakes/their strategy may not be optimal strategy

Supervised learning is not enough

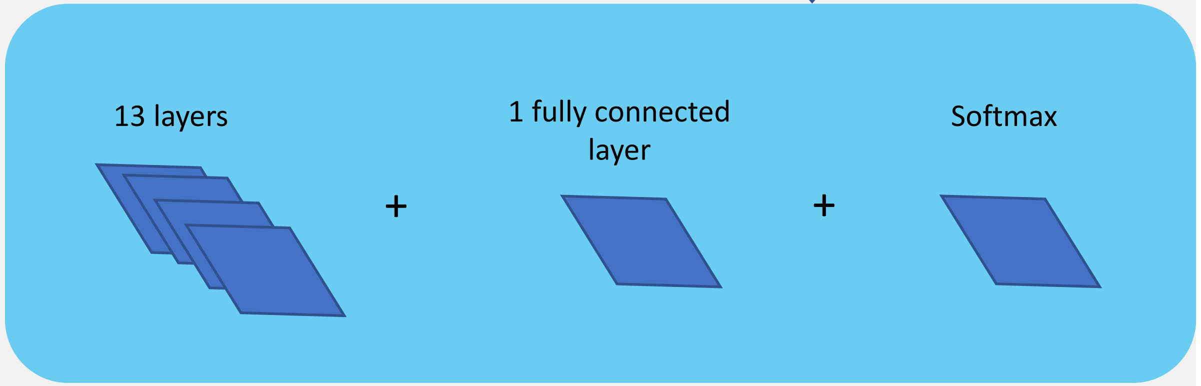
(Smiling) Puppy picture

Pixels

Human expert positions



48 feature planes
(each 19 X 19)
19 X 19 X 48



In the picture, there is a
- (Smiling) Puppy (80%)
- (Angry) puppy (60%)
- Kittie (10%)
- Baby (1%)
- …

Human experts will take an move in
- Position 1 (56%)
- Position 2 (30%)
- Position 3 (20%)
- …

2.1 AlphaGo: Policy and Policy Network

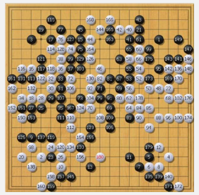
Policy Based Learning

$P(a|s)$ **Formally, a policy maps states to actions**

- In policy gradient framework, it is a probability distribution over all states and actions (Contrast with the value framework)
- Policy will tell the probability of I choose a particular action under current state
- No value function, states and actions can be continuous and infinite
- Often parameterized, a function $P_\theta(a|s)$
- Training becomes an optimization problem

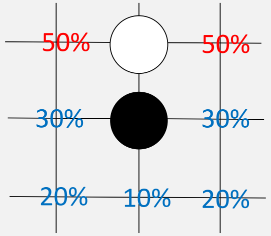
Policy Network in AlphaGo

Take board position **s** as input



$P_\theta(a|s)$

Action probability distribution/matrix



50%	n/a	50%
30%	n/a	30%
20%	10%	20%

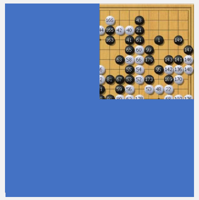
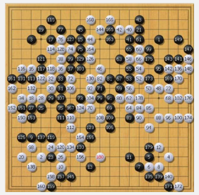
Training:
Stochastic gradient ascent to maximize the log likelihood

Rollout Policy vs. Supervised Learning Policy

Trade off between speed and accuracy

Choose an action	Rollout Policy	SL Policy
Speed	$2\mu s$	$3ms$
Accuracy	24.4%	57%

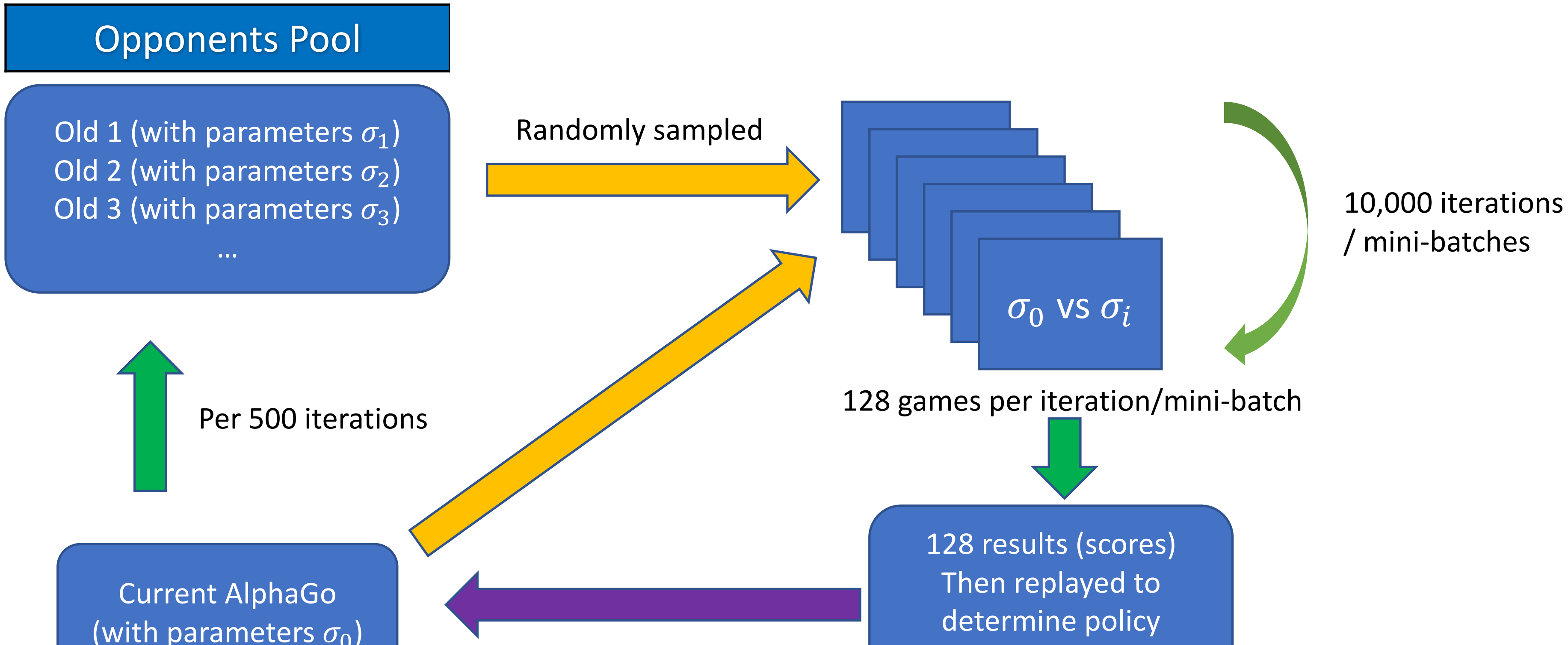
The key differences are

Structure	Rollout Policy	SL Policy
Softmax function	Linear	Non-linear
Feature fed into CNN	Small feature size (A simple demo) 	Full size (19 X 19 X 48) 
Other techniques	*Last good reply heuristic*	
Notation	$P_\pi(a|s)$	$P_\sigma(a|s)$

2.2 Reinforcement Learning: Policy Network Iterations

The aim here is to allow the policy to be improved by letting the AI play against itself

$$P_\sigma(a|s) \Rightarrow P_\rho(a|s), \sigma\ and\ \rho\ are\ weight\ parameters$$



$$\Delta\rho \propto \frac{\partial \log p_\rho(a_t|s_t)}{\partial \rho} z_t$$

$$z_t = \pm 1$$

2.3 Reinforcement Learning: Value Network and Position Evaluation

Now we have a better policy (strategy), we want to predict the outcome of game when we make a move

i.e. the probability of me winning this game

Value Function

$$v^p(s) = \mathbb{E}[z_t | s_t = s,\ a_{t\ldots T} \sim p]$$

- **Interpretation:** the value (chances of win) of the current state after I make a move under the policy p.
- **Problem:** we do not know the optimal value function under perfect play $v^*(s)$
- **Solution:** use approximation
  - $v_\theta(s) \approx v^{p_\rho}(s) \approx v^*(s)$

Training

- Parameterized value function $v_\theta(s)$ with weights θ
- We know the game results for a given state (board position) under the strongest policy p_ρ, i.e. $v_\theta(s)$.
- **Optimization problem:** optimize θ so that $v_\theta(s)$ is close to $v^{p_\rho}(s)$
- **Approach:** standard regression (projection) method
- Minimize Mean Squared Errors:
  - $\left(v_\theta(s)\ -\ v^{p_\rho}(s)\right)^2$ or $\left(v_\theta(s)\ - z^k\right)^2$ where $z^k = \pm 1$

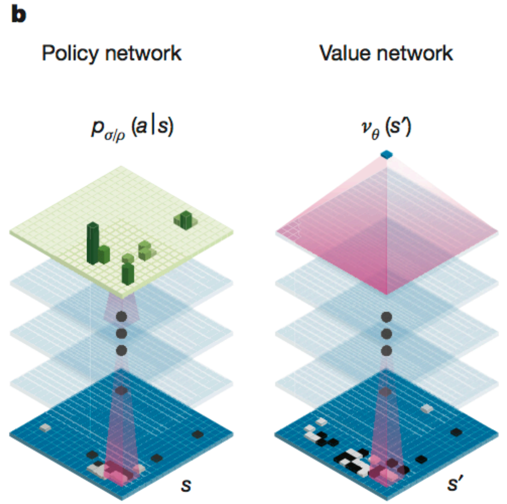
Overfitting

Naïve approach leads to overfitting

- **Training:** Mean Squared Errors of 0.19
- **Testing:** Mean Squared Errors of 0.37

Solution and approach

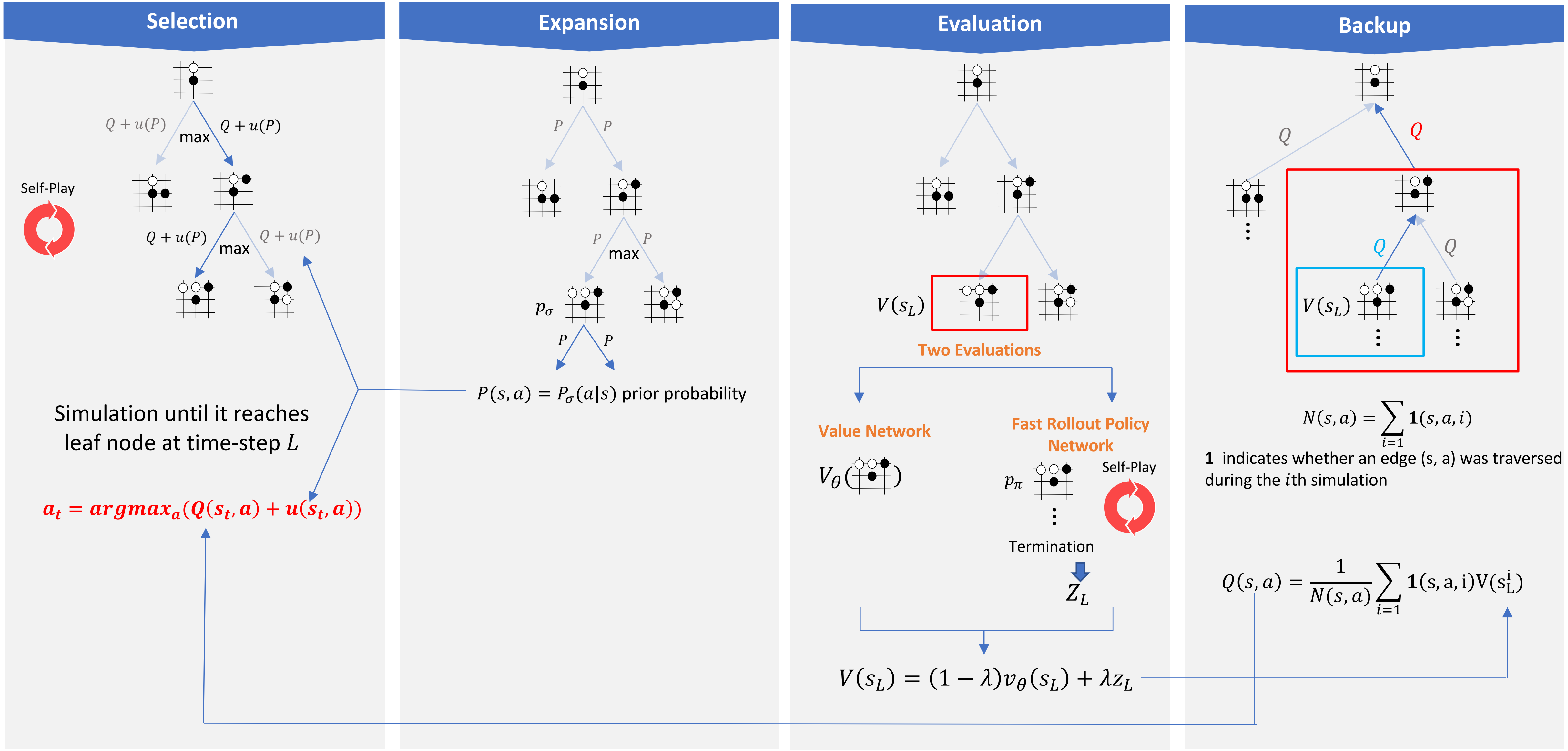
- A new self-play dataset consisting of 30 million distinct positions, each sampled from a separate game
- Each game between the RL policy network and itself
- MSEs: 0.226 (Training) and 0.234 (Testing)



(Silver et al. 2016)

2.4 Monte Carlo Tree Search: Search with Policy and Value Networks

Asynchronous Policy and Value Monte Carlo Tree Search (APV-MCTS)



AlphaGo Zero

Simple Neural Network Structure
Completely tablua Rasa

An “interesting” fact about AlphaGo Zero:
The system consists of only 4 TPUs,
each of which is 15-30 times more efficient than GPUs in performance per-watt
And 64 GPUs, 19 CPUs.

3.1 Deep Neural Network- Structure Breakdown

Single Neural Network Architecture

$$(P, v) = f_\theta(s)$$

Policy Network

$p_a = \Pr(a|s)$ probability of selecting each move from the current position

Value Network

v scalar evaluation, estimating the probability of current players winning from the current position

Core RL Concepts

Policy Evaluation → Value Function

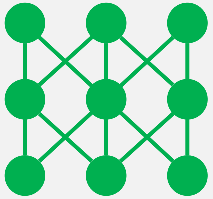
Policy Iteration

Policy Improvement

Training Pipeline

Reinforcement Learning

Neural Network

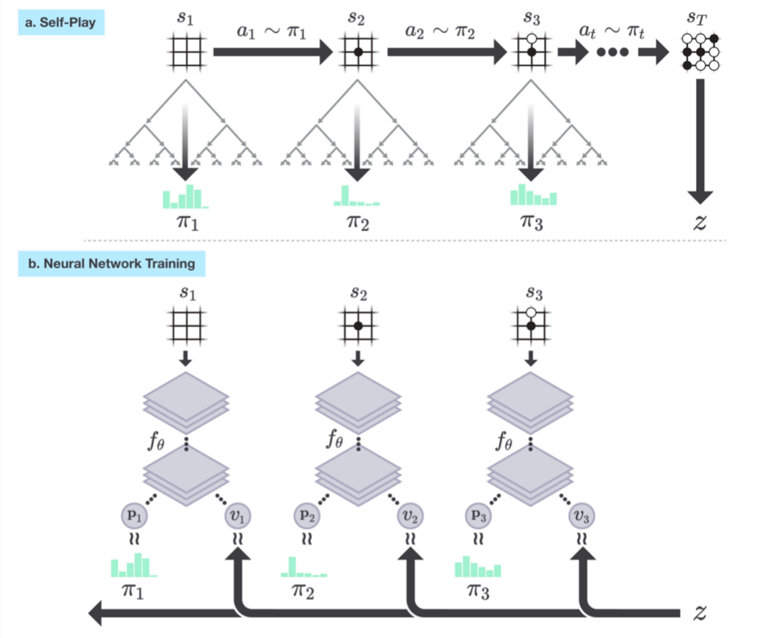


Self-Play

Policy Evaluation

$f_\theta(s) \Rightarrow$ MCTS $\Rightarrow$ π_t, a move is selected according to policy π_t

Terminal state s_T will give us a game winner Z



Policy Improvement

At time t, feed the board position s_t into policy $f_\theta(s) = f_\theta(s_t)$, which gives us p_t and v_t.

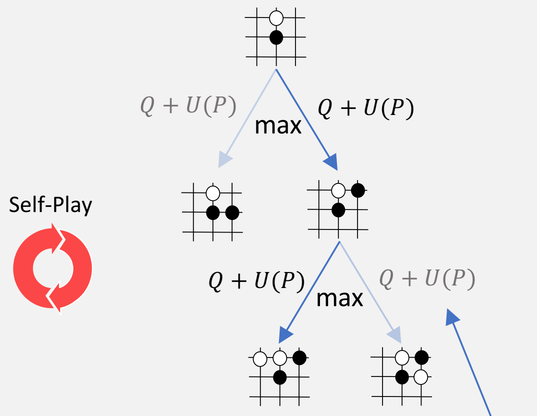
Optimization problem: optimize weight parameters θ to minimize prediction errors between $\boldsymbol{p_t}$ **-** $\boldsymbol{\pi_t}$ **and** $\boldsymbol{v_t - Z_t}$

Minimize Loss Function: $l = (z - v)^2 - \pi^T \log \mathbf{p} + \mathbf{c}||\theta||^2$

3.2 Monte Carlo Tree Search: Search with a Single Neural Network

Asynchronous Policy and Value Monte Carlo Tree Search (APV-MCTS)

Selection



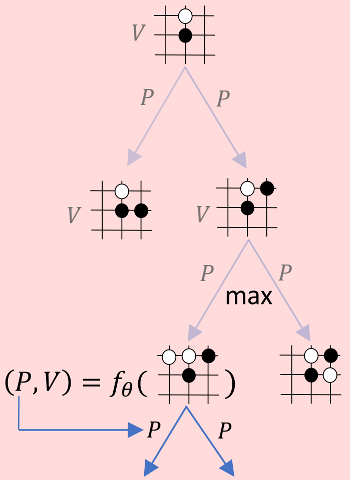
Simulation until it reaches leaf node at time-step L

We select but we do not act

$$a_t = argmax_a(Q(s_t, a) + U(s_t, a))$$

Expansion and Evaluation

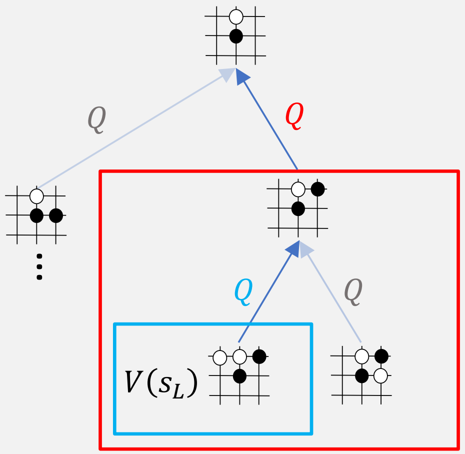
Repeat



$P(s,a) = P_\sigma(a|s)$ prior probability

V is the probability value that I win from the current board position S_t at time t (Value function)

Backup

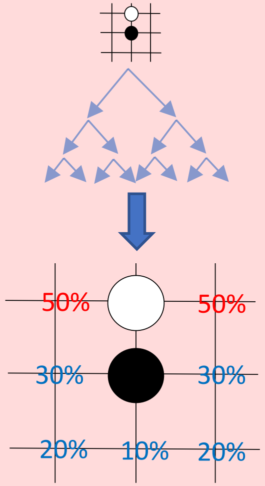


$$N(s,a) = N(s,a) + 1$$

$$Q(s,a) = \frac{1}{N(s,a)} \sum_{s'|s,a \to s'} V(s')$$

Play

After the end of the search iterations, AlphaGo Zero will make a move



$$\pi(a|s_0) = \frac{N(s_0,a)^{\frac{1}{\tau}}}{\sum_b N(s_0,b)^{\frac{1}{\tau}}}$$

Once an action is choose, that sub-node becomes root, children remains and the rest of the old tree is discarded

4. Humans, AlphaGo and AlphaGo Zero

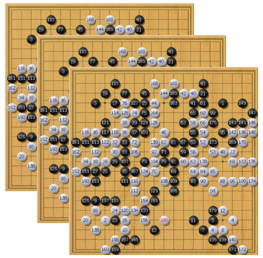
Humans

They develop new policies only when they become masters in Go

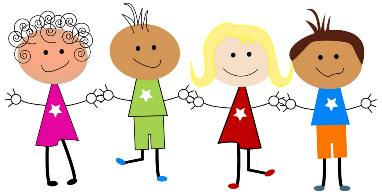
Ancient Master / Experts

Dozens of manuals/books

Heritage from ancient knowledge in thousands of years



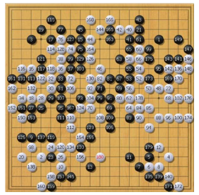
Kids



The problem is that there is limited evaluation process children will not (often are not allowed) to question ancient knowledge (mostly because of the Asian culture)

AlphaGo

Supervised Learning



Self-play

Policy Evaluation

Humans are right

Humans are wrong

Policy Improvement

AlphaGo Zero

1. Only basic rules
2. Start from completely random play

Self-play

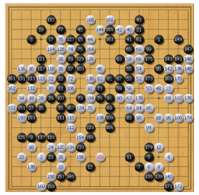
Policy Evaluation

I am right

I am wrong

Policy Improvement

Self-developed manuals



- Concepts of shapes, territory, influence
- Joseki
- Fuseki
- Tesuji
- Sente
- Shicho

5. Discussions

Human vs. Artificial Intelligence

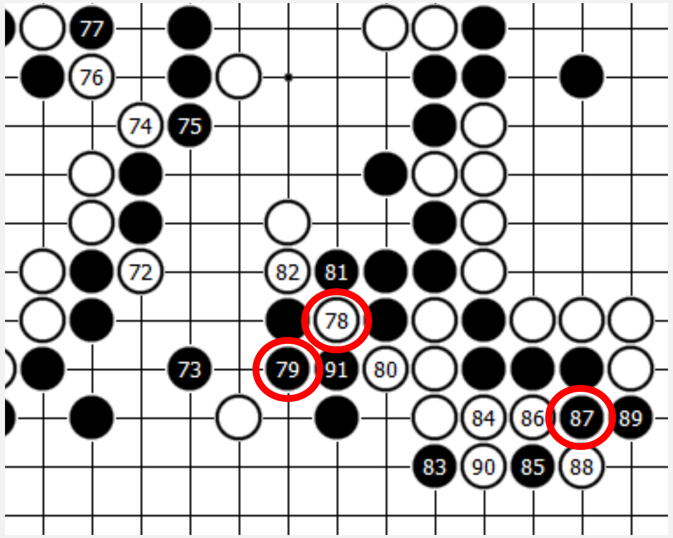
Humans in Go game

- Humans are often wrong
- Master manuals are more like guidance rather than mandatory knowledge
- Self-evaluation and improvement are key to learning
- The concept of tabula rasa is crucial in learning theories

AI in Go game

- Algorithms are much more important than data
- People tend to assume that machine learning is all about big data and massive computations, THAT IS WRONG!
- AlphaGo Zero does not use any human data whatsoever, it always has the opponent at just right level (self-play), and improves itself from self-learning
- Yet it performs much better, and significantly less computational requirement

The only game that AlphaGo resigned



- AlphaGo (Black) calculates that Lee Sedol has 0.01% chances to make move 78
- Policy informed AlphaGo that move 79 had a winning probability of 70%
- It realised that the winning probability was actually only 55% after move 87
- Often considered as a “bug” in MCTS

6. AlphaZero: General Version

Generalize AlphaGo Zero in board games

AlphaGo Zero vs. AlphaZero

	AlphaGo Zero	AlphaZero
Value Function	Binary win/loss Probability of Winning	Expected outcome (Chess has win, loss, draw)
Rotation and Reflection	Invariance (faster training)	Variance (Asymmetric rules)
Policy Improvem ent	Current best player vs. New player after each iteration If win by 55% then update the policy	Updated continually, even during the iterations

Neural network architecture in different games

	Chess	Shogi	Go
Input Feature	119	362	17
Policy Plane	8 X 8 X 73	9 X 9 X 139	19 X 19 + 1
Training Time	9h	12h	34h
Training Games	44 million	24 million	21 million