Data-Driven Reinforcement Learning

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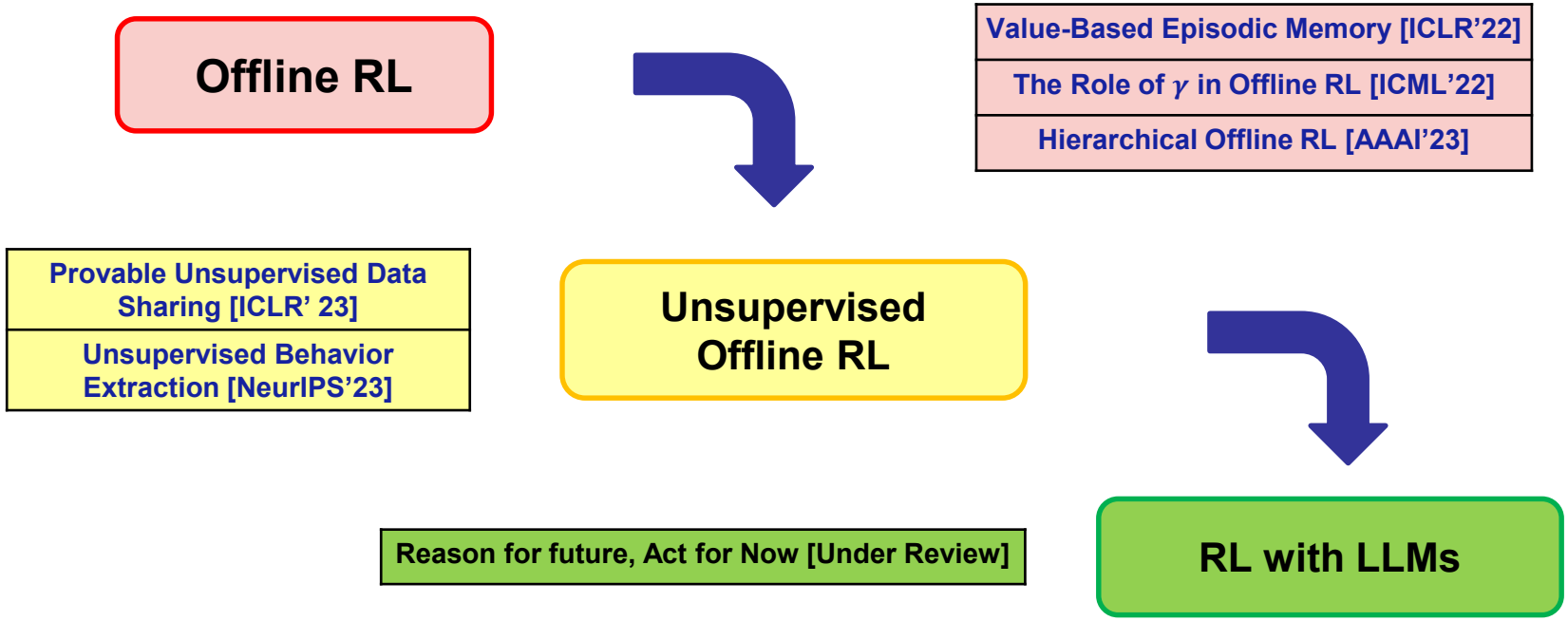
Data-Driven Reinforcement Learning

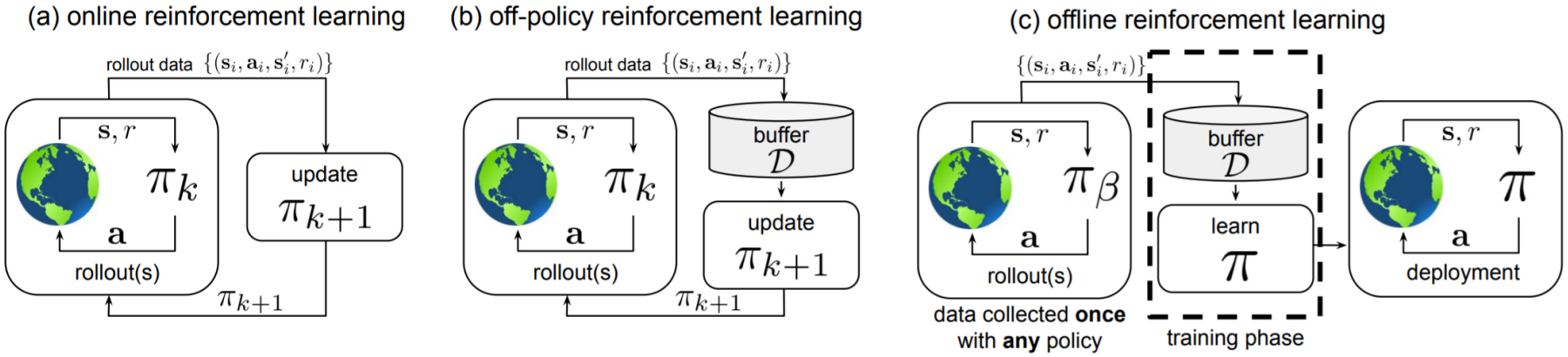


Why Offline Reinforcement Learning?

- Data is cheap, exploration is expensive

What is Offline Reinforcement Learning?

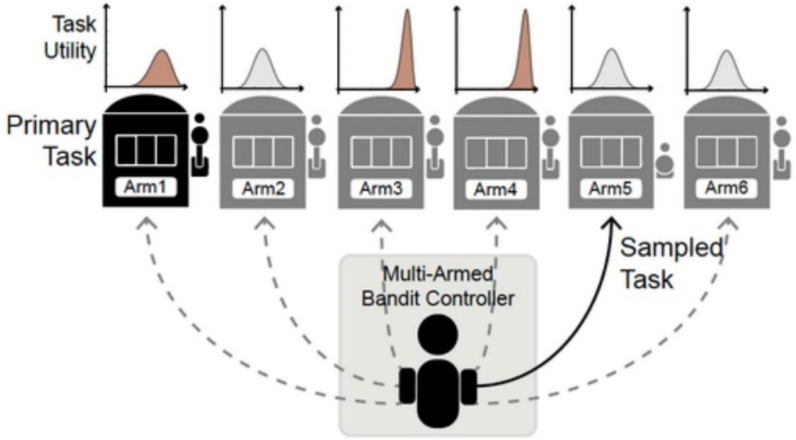
- Decoupling learning and exploration



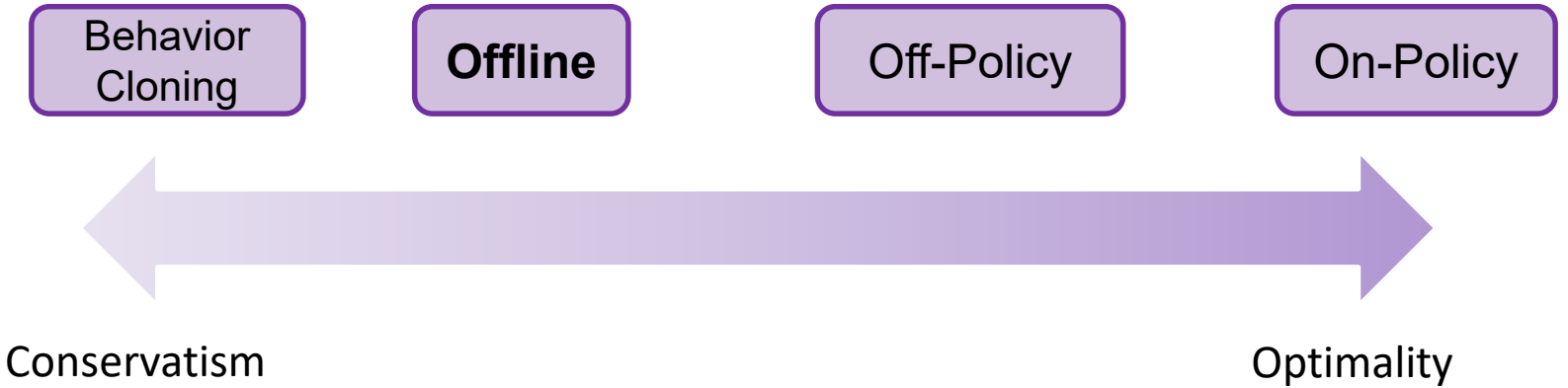
The Key Ingredient: Pessimism

- Avoid bad decision-making
- Select the most "not-bad" action

$$\text{argmax}_a \, \mu(a) - k\sigma(a)$$



Offline Reinforcement Learning



Value-Based Episodic Memory [ICLR'22]

- Bellman expectation operator for Q^{π}

$$\mathcal{T}^{\pi}V(s) = \mathbb{E}_{\substack{a\sim\pi(\cdot|s) \\ s\prime\sim p(\cdot|s,a)}}[r(s,a) + \gamma V(s')]$$

- Bellman optimality operator for Q^{*}

$$\mathcal{T}V(s) = \max_{\mathrm{a}} \mathbb{E}_{s\prime\sim p(\cdot|s,a)}[r(s,a) + \gamma V(s')]$$

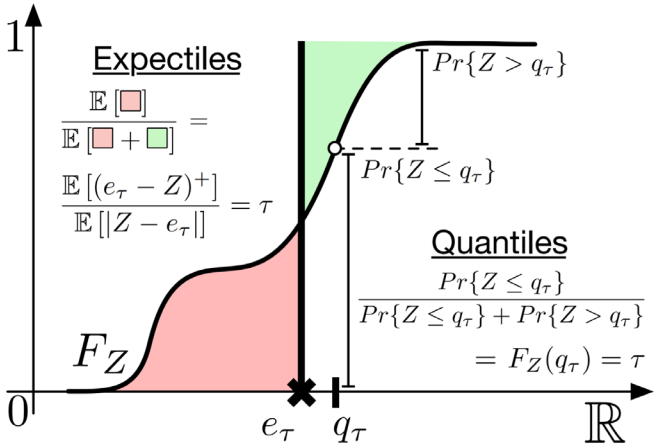
Expectiles

- A similar statistic as quantile
  - Quantile: minimizer of quantile regression loss

$$QR(q;\mu,\tau) = \mathbb{E}_{Z\sim\mu}\left[\left(\tau\mathbb{1}_{\tau>q} + (1-\tau)\mathbb{1}_{\tau\le q}\right)|Z-q|\right]$$

  - Expectile: minimizer of expectile regression loss

$$ER(q;\mu,\tau) = \mathbb{E}_{Z\sim\mu}\left[\left(\tau\mathbb{1}_{\tau>q} + (1-\tau)\mathbb{1}_{\tau\le q}\right)(Z-q)^2\right]$$



Expectile V-learning

- Bellman expectile operator $\mathcal{T}_\tau^\mu$

$$\left(\mathcal{T}_\tau^\mu\right)V(s) \coloneqq argmin\ \mathbb{E}_{a\sim\mu}[\tau[\delta(s,a)]_+^2 + (1-\tau)[-\delta(s,a)]_+^2]\,,$$

where $\delta(s,a) = \mathbb{E}_{s'}[r(s,a) + \gamma V(s') - v], [\cdot]_+ = \max\{0,\cdot\}$.

- $\tau = 1/2$: Bellman expectation operator

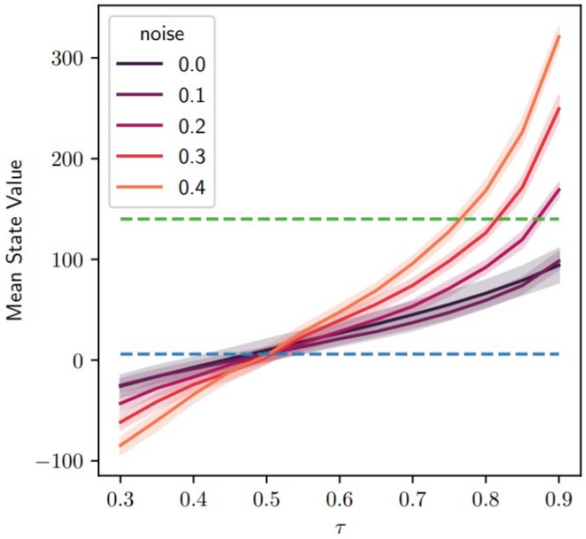
$$\left(\mathcal{T}_{1/2}^\mu\right)V(s) = \mathbb{E}_{a\sim\mu}[r(s,a) + \gamma V(s')]$$

- $\tau \to 1^-$: Bellman optimality operator

$$\lim_{\tau\to 1^-}\left(\mathcal{T}_\tau^\mu\right)V(s) = \max_a r(s,a) + \gamma V(s')$$

Trade-offs with different τ

τ achieve a trade-off between generalization and conservatism



τ	$\|V - V^*\|_\infty$
0.5	3.61 ± 0.24
0.6	2.84 ± 0.22
0.7	2.10 ± 0.22
0.8	1.29 ± 0.24
0.9	0.40 ± 0.15
0.95	1.07 ± 0.18
0.98	2.02 ± 0.18

Evaluation error on a random MDP with random noise applied on the operator

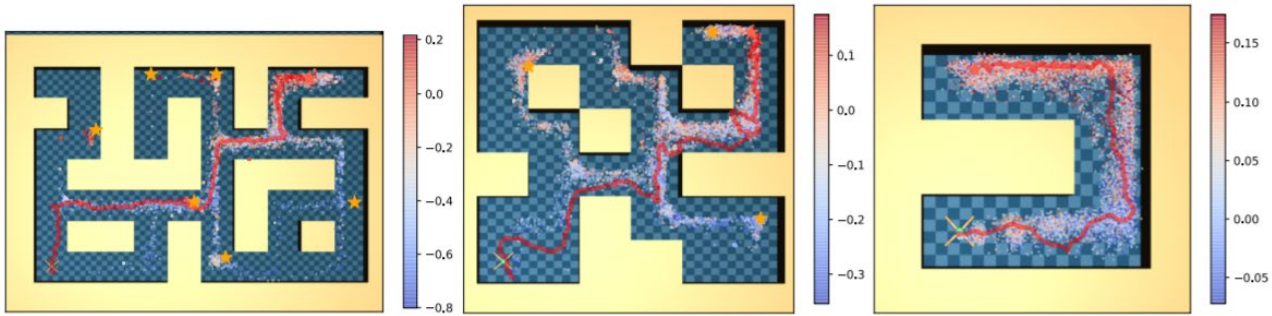
Experiments

- Evaluation on D4RL tasks

Type	Env	VEM(Ours)	VEM(τ=0.5)	BAIL	BCQ	CQL	AWR
fixed	umaze	**87.5±1.1**	85.0±1.5	62.5 ± 2.3	78.9	74.0	56.0
play	medium	**78.0±3.1**	71.0±2.5	40.0 ± 15.0	0.0	61.2	0.0
play	large	**57.0±5.0**	45.0±2.5	23.0±5.0	6.7	11.8	0.0
diverse	umaze	78.0 ± 1.1	75.0±5.0	75.0±1.0	55.0	**84.0**	70.3
diverse	medium	**77.0±2.2**	60.0±5.0	50.0±10.0	0.0	53.7	0.0
diverse	large	**58.0 ± 2.1**	48.0±2.7	30.0±5.0	2.2	14.9	0.0
human	door	**11.2±4.2**	6.9±1.1	0.0±0.1	-0.0	9.1	0.4
human	hammer	**3.6±1.0**	2.5±1.0	0.0±0.1	0.5	2.1	1.2
human	relocate	1.3±0.2	0.0±0.0	0.0±0.1	0.5	**2.1**	-0.0
human	pen	65.0±2.1	55.2±3.1	32.5±1.5	**68.9**	55.8	12.3
cloned	door	**3.6±0.3**	0.0±0.0	0.0±0.1	0.0	3.5	0.0
cloned	hammer	2.7±1.5	0.5±0.1	0.1±0.1	0.4	**5.7**	0.4
cloned	pen	**48.7±3.2**	27.8±2.2	46.5±3.5	44.0	40.3	28.0
expert	door	**105.5±0.2**	104.8±0.2	104.7±0.3	99.0	-	102.9
expert	hammer	**128.3±1.1**	102.3±5.6	123.5±3.1	114.9	-	39.0
expert	relocate	**109.8±0.2**	101.0±1.5	94.4±2.7	41.6	-	91.5
expert	pen	111.7±2.6	115.2±1.3	**126.7±0.3**	114.9	-	111.0
random	walker2d	6.2±4.7	6.2±4.7	3.9±2.5	4.9	**7.0**	1.5
random	hopper	**11.1±1.0**	10.8±1.2	9.8±0.1	10.6	10.8	10.2
random	halfcheetah	16.4±3.6	2.6±2.1	0.0±0.1	2.2	**35.4**	2.5
medium	walker2d	74.0±1.2	16.6±0.1	73.0±1.0	53.1	**79.2**	17.4
medium	hopper	56.6±2.3	56.6±2.3	**58.2±1.0**	54.5	58.0	35.9
medium	halfcheetah	**47.4±0.2**	45.3±0.2	42.6±1.2	40.7	44.4	37.4

Experiments

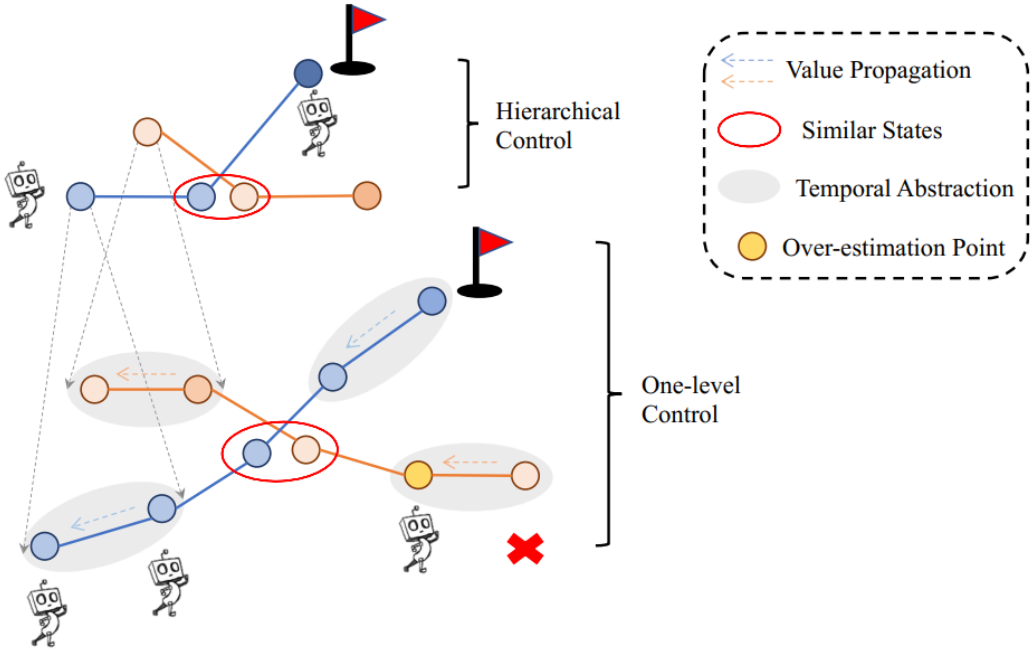
- Evaluation on D4RL tasks

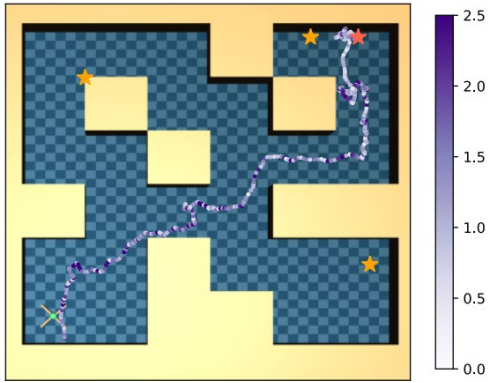


(a) Large (b) Medium (c) Umaze

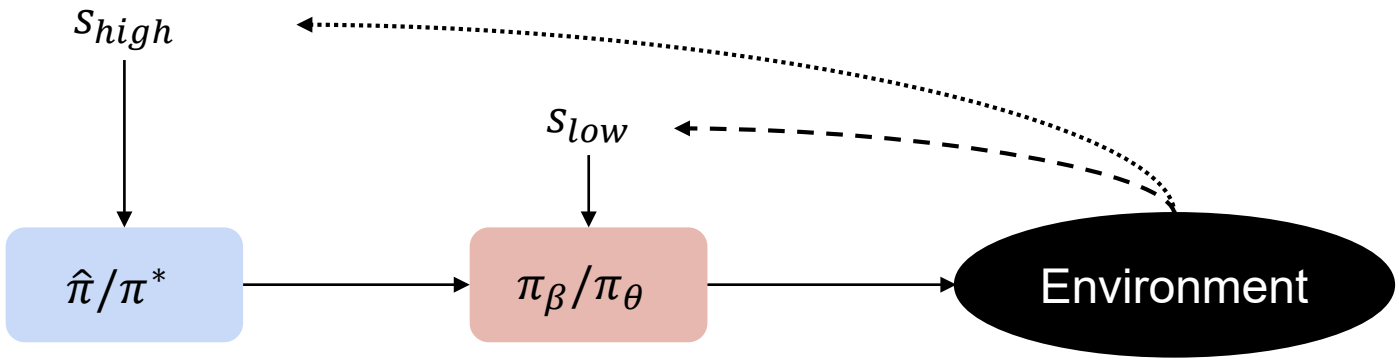
Figure 4: Visualization of the value estimation in various AntMaze tasks. Darker colors correspond to the higher value estimation. Each map has several terminals (golden stars) and one of which is reached by the agent (the light red star). The red line is the trajectory of the ant.

Flow to control [AAAI'23]





Error Decomposition



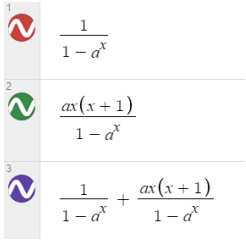
$$\text{SubOpt}(\widehat{\pi}_\theta) = \underbrace{J(\widehat{\pi}_\beta) - J(\widehat{\pi}_\theta)}_{\text{Primitive Error}} + \underbrace{J(\pi^*_\beta) - J(\widehat{\pi}_\beta)}_{\text{Offline Error}} + \underbrace{J(\pi^*) - J(\pi^*_\beta)}_{\text{Representation Error}}.$$

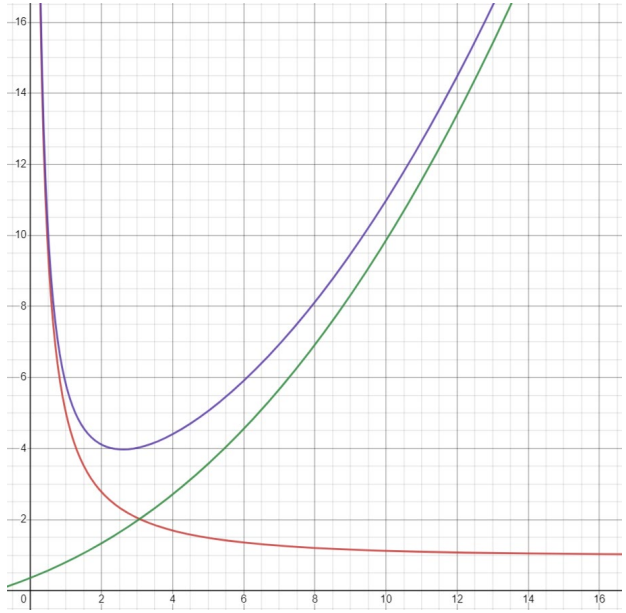
Error Decomposition

Theorem 1. *Under the condition in Lemma 1, 2 and 3, the suboptimality of a policy learned in the hyper-MDP with Algorithm 2 satisfies*

$$\text{SubOpt}(\widehat{\pi}_\theta) \leq \frac{2Cr_{\max}}{(1-\gamma)(1-\gamma^c)}\sqrt{\frac{c^\dagger d^3 \zeta}{N}} + \frac{\gamma c(c+1)r_{max}}{(1-\gamma)(1-\gamma^c)}(\varepsilon_\Omega + \varepsilon_\theta), \quad (4)$$

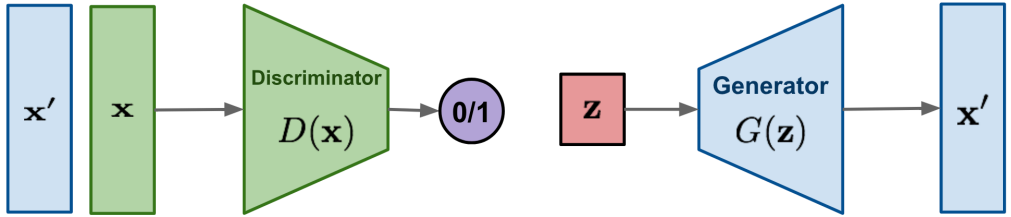
with high probability $1-2\delta$.



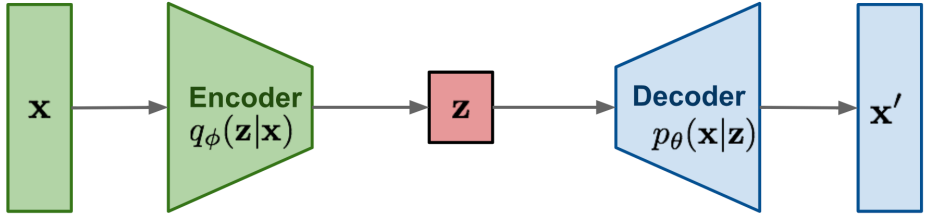


Flow-based Generative Models

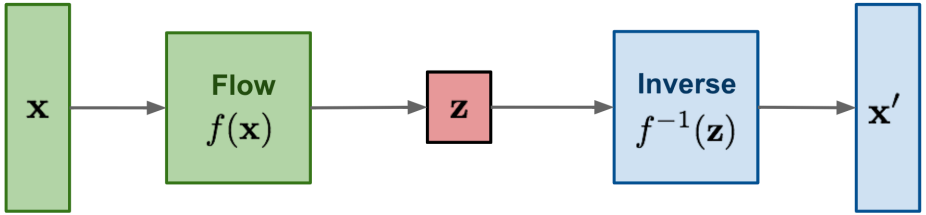
GAN: minimax the classification error loss.



VAE: maximize ELBO.

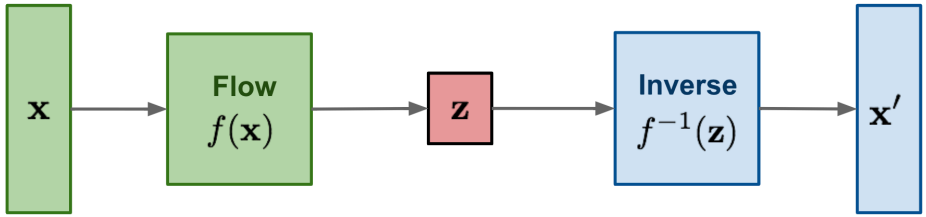


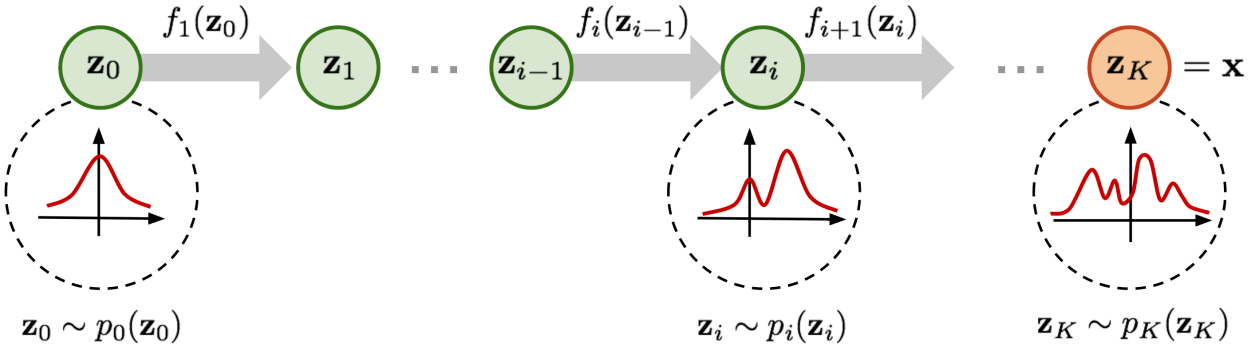
Flow-based generative models: minimize the negative log-likelihood



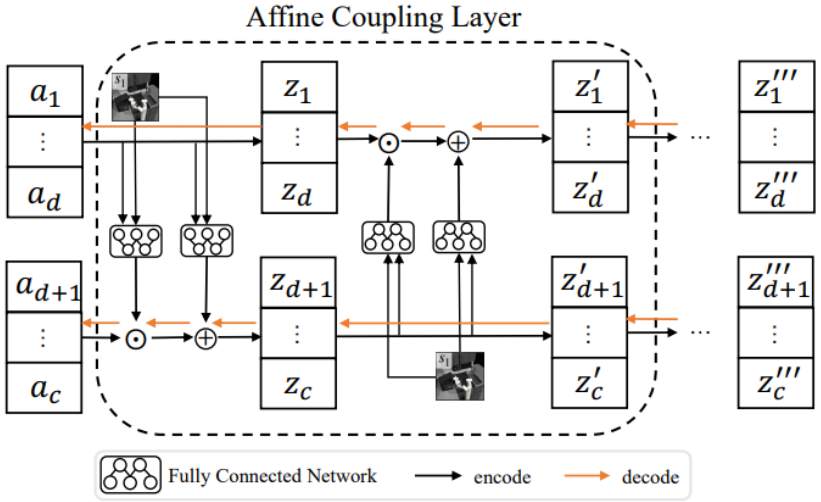
Flow-based Generative Models

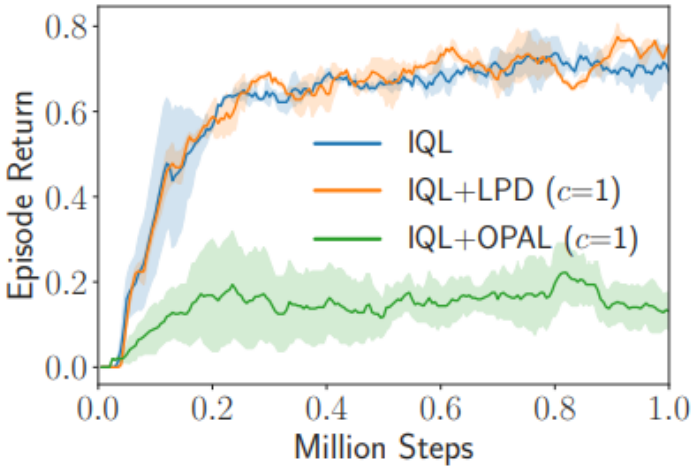
Flow-based generative models: minimize the negative log-likelihood





Flow-based Generative Models

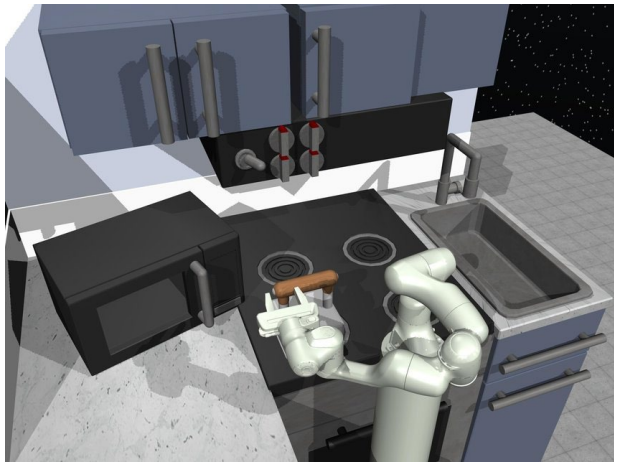




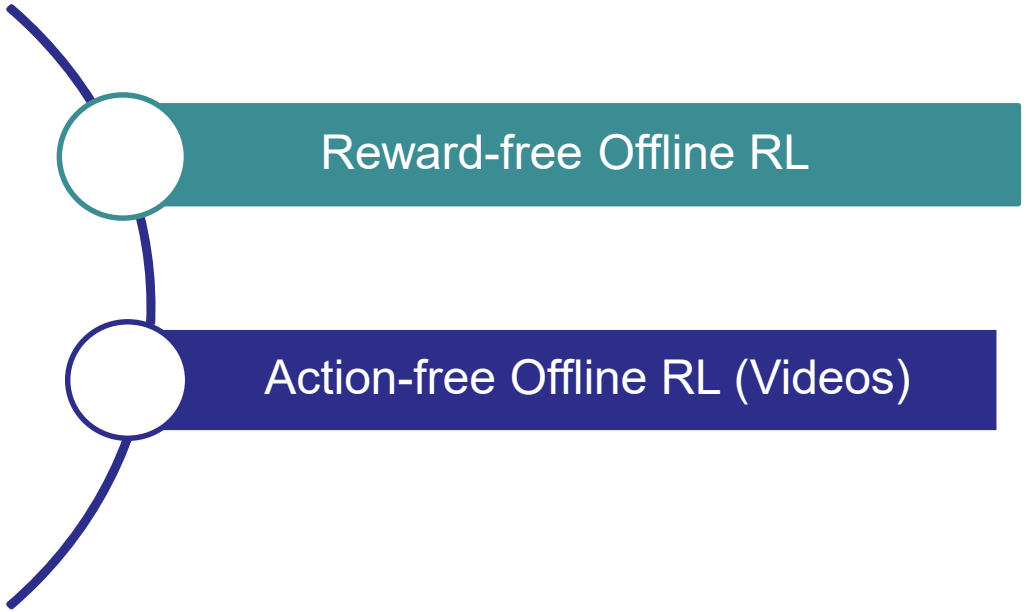
(c) Performance

Experiments

Type	Env	IQL+LPD	IQL	CQL	OAMPI	TD3+BC	EMAQ
partial	kitchen	**74.9±1.1** ↑	46.3	49.8	35.0±3.3	7.5±1.3	**74.6±0.6**
mixed	kitchen	**69.2±1.9** ↑	51.0	51.0	47.5±4.1	1.5±0.2	**70.8±2.3**
complete	kitchen	**75.0±0.7** ↑	62.5	43.8	10.0±1.9	23.5±2.5	36.9±3.7
fixed	Antmaze-umaze	**93.0±1.3** ↑	87.5	74.0	64.3±4.6	78.6±4.4	**91.0±4.6**
play	Antmaze-medium	**74.7±2.2** ↑	**71.2**	10.6	0.0±0.0	33.6±2.2	0.0±0.0
play	Antmaze-large	**56.2±3.6** ↑	39.6	0.2	0.3±0.1	21.4±3.3	0.0±0.0
diverse	Antmaze-umaze	81.6±2.0 ↑	62.2	84.0	60.7±3.9	71.4±4.6	**94.0±2.4**
diverse	Antmaze-medium	**83.7±1.6** ↑	70.0	3.0	0.0±0.0	34.7±2.5	0.0±0.0
diverse	Antmaze-large	**52.8±1.1**↑	47.5	0.0	0.0±0.0	25.9±2.7	0.0±0.0
human	door	**15.1±2.5** ↑	4.3	9.9	2.8±0.1	0.0±0.0	-
human	hammer	3.3±0.7 ↑	1.4	**4.4**	3.9±0.2	0.9±0.1	-
human	pen	63.1±1.6	**71.5**	37.5	54.6±4.6	39.0±3.6	-
cloned	door	**8.1±1.0** ↑	1.6	0.4	0.4±0.1	0.0±0.0	0.2±0.3
cloned	hammer	2.1±0.2	2.1	2.1	2.1±0.1	0.3±0.1	1.0±0.7
cloned	pen	**65.8±2.7** ↑	37.3	39.2	60.0±5.2	25.1±1.9	27.9±3.7



Unsupervised Offline RL

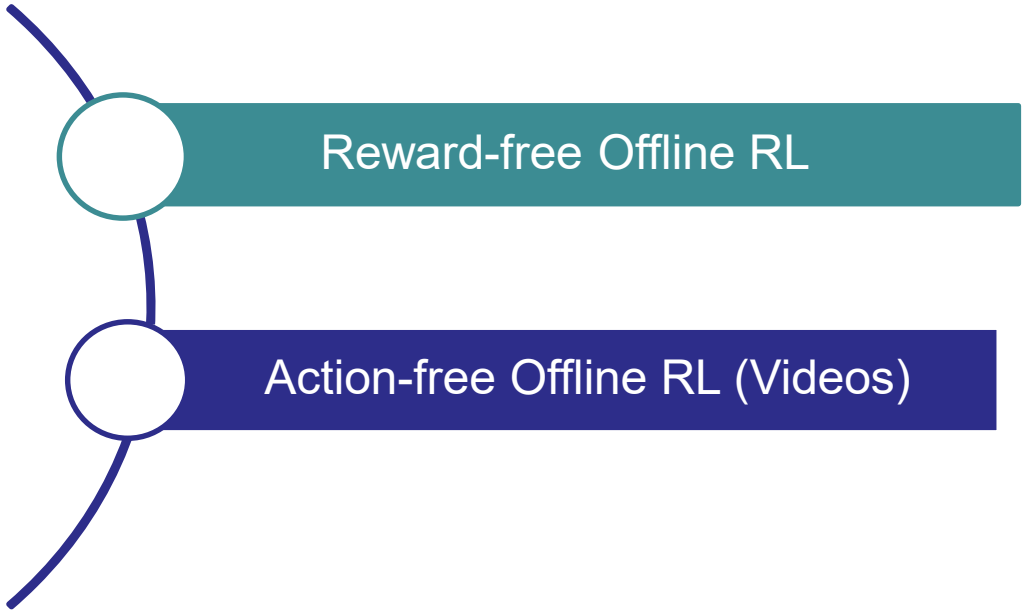


Provable Unsupervised Data Sharing [ICLR' 23]

Unsupervised Behavior Extraction [NeurIPS'23]

Passive RL with State-Centric Planning [Under Review]

Unsupervised Offline RL



Provable Unsupervised Data Sharing [ICLR' 23]

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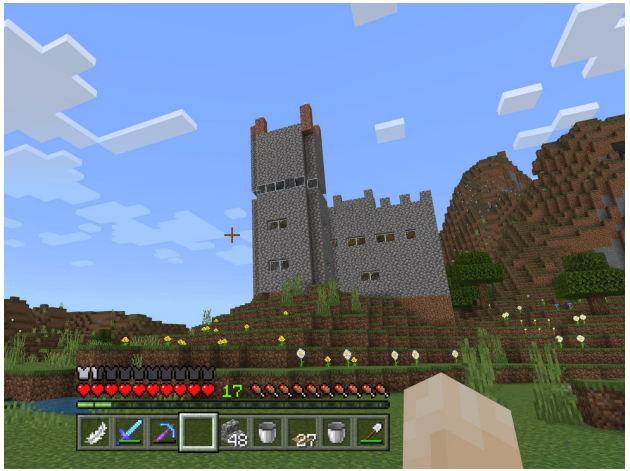
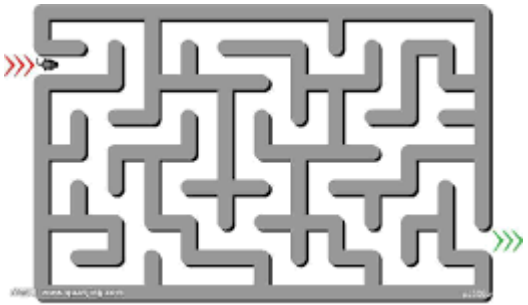
Motivation: Can we bring in even more data?

- Abundant reward-free data, containing useful human behaviors
- How to extract them effectively from offline data?



Motivation

- Human conduct a behavior based on some intentions – A reward function, but we don't know them
- We can learn similar behaviors by randomly sampling from the distribution of intentions
- In fact, we can use **random** intentions



Random Neural Networks as Priors

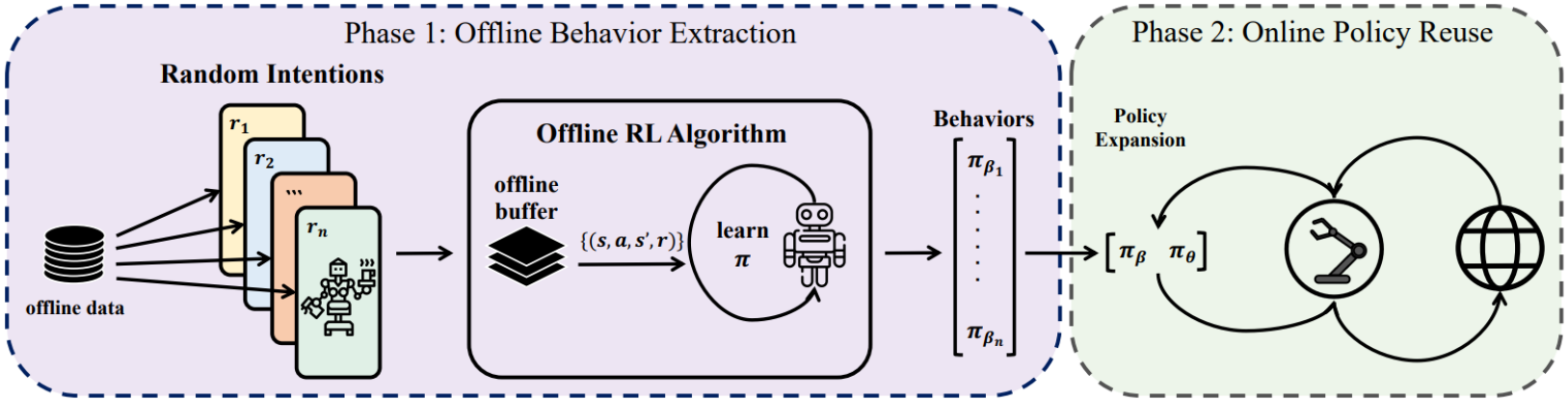


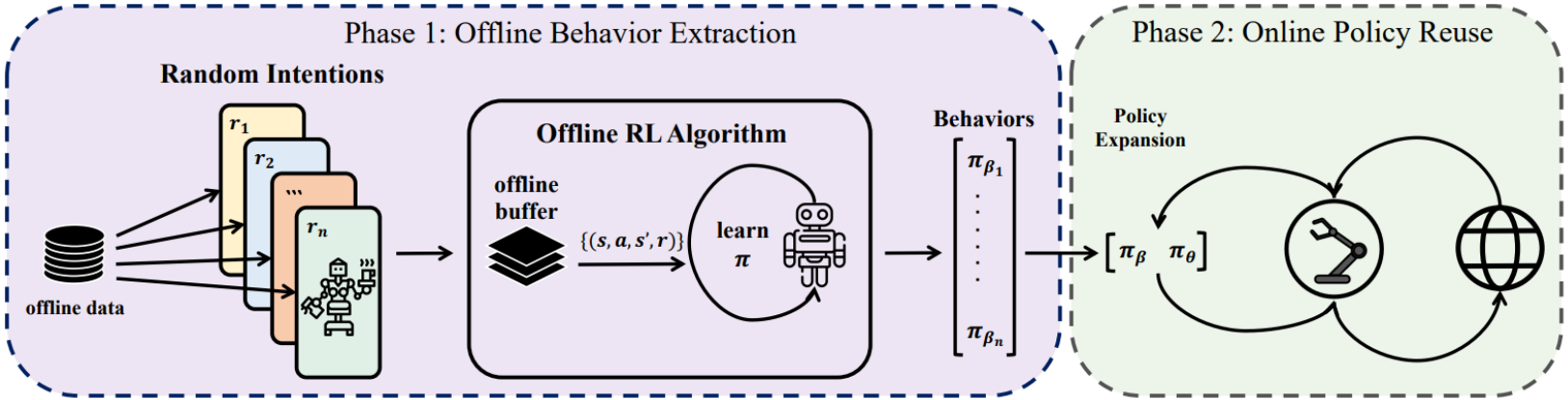
Figure 2: The framework of UBER. The procedure consists of two phases. In the first phase, we extract diverse and useful behaviors from the offline dataset with random rewards. In the second phase, we reuse previous behavior to accelerate online learning.

Policy Composition

- Policy set $\Pi = [\pi_\beta, \pi_\theta]$
- Utility $P_{\mathbf{w}}[i] = \frac{\exp(Q_\phi(s, a_i)/\alpha)}{\sum_j \exp(Q_\phi(s, a_j)/\alpha)}, \quad \forall i \in [1, \cdots K]$
- Composition

$$\tilde{\pi}(a|s) = [\delta_{a\sim\pi_\beta(s)}, \delta_{a\sim\pi_\theta(s)}]\mathbf{w}, \quad \mathbf{w} \sim P_{\mathbf{w}}$$

UBER: Unsupervised Behavior Extraction



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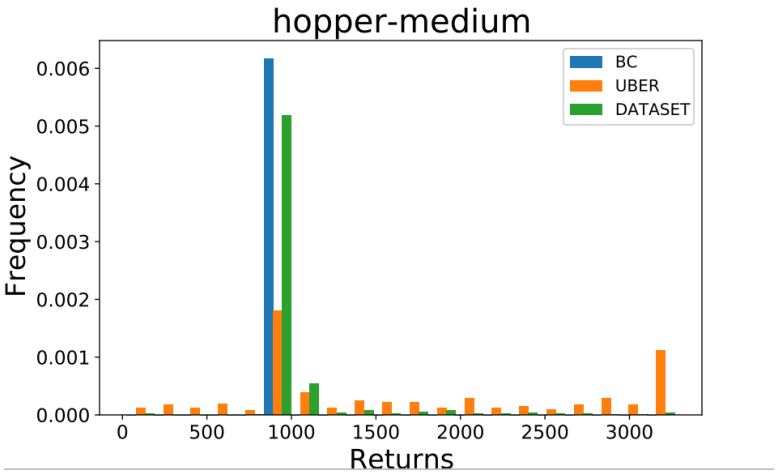
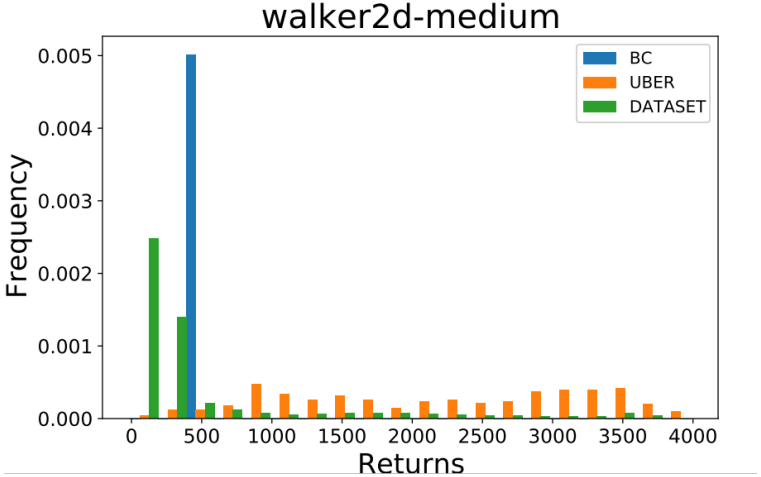
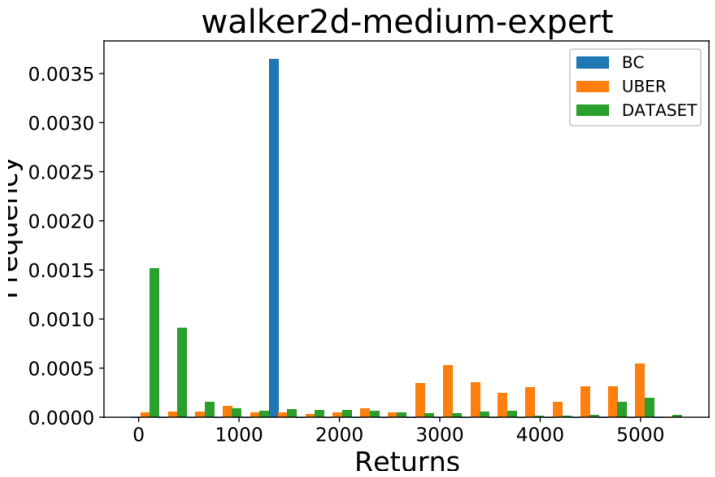
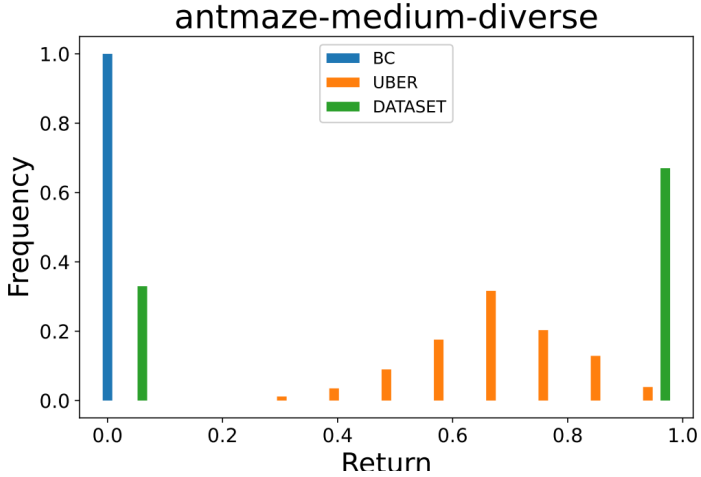
Experiments: Diversity



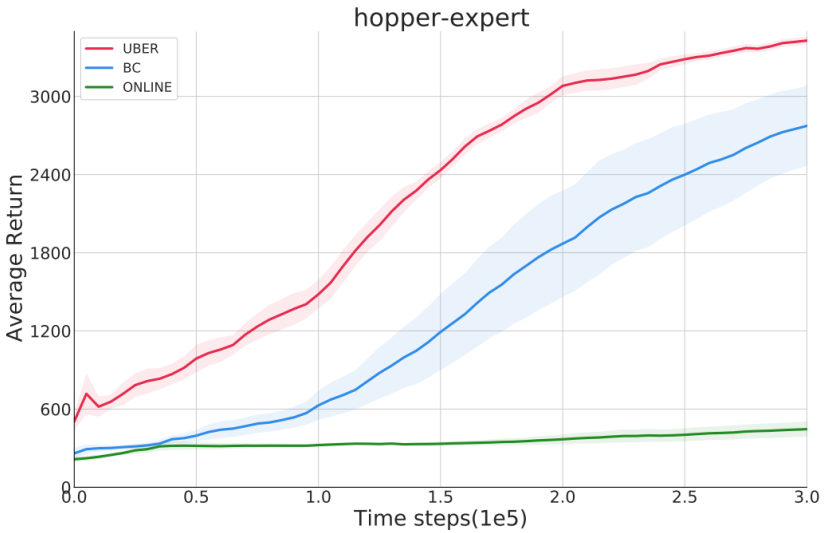


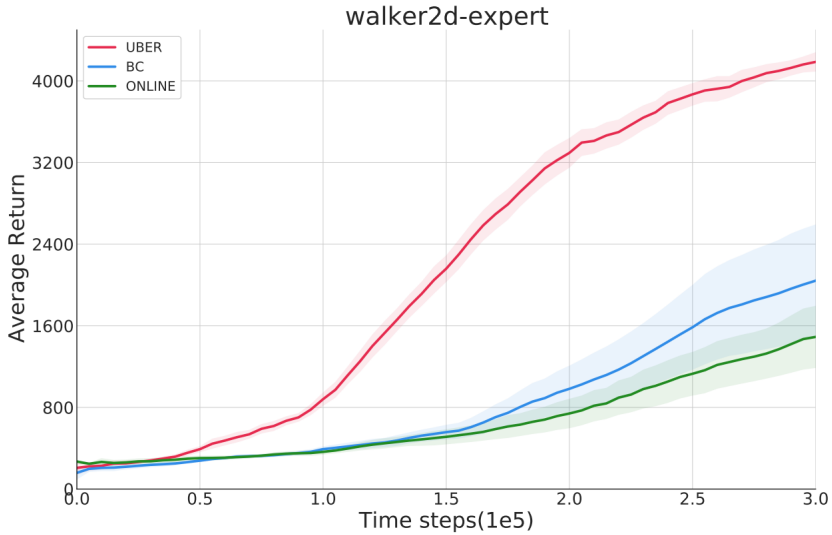
Experiments: Diversity



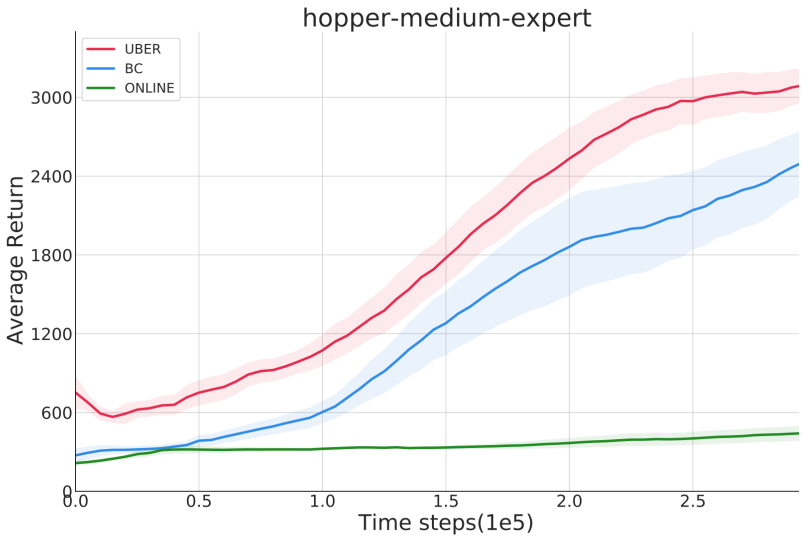


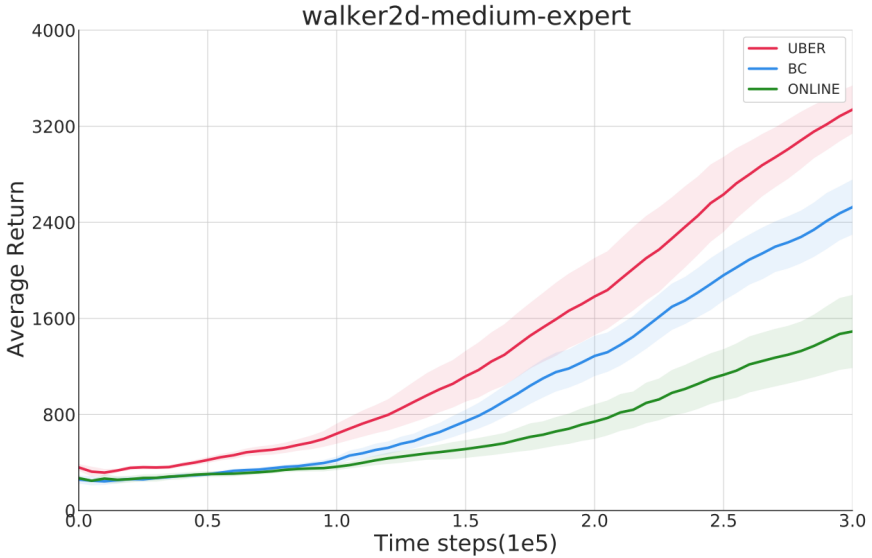
Experiments: Usefulness





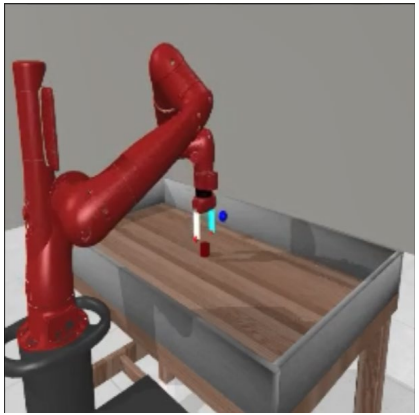
Experiments: Usefulness

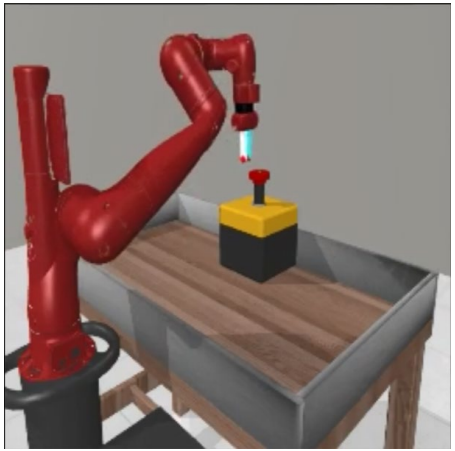




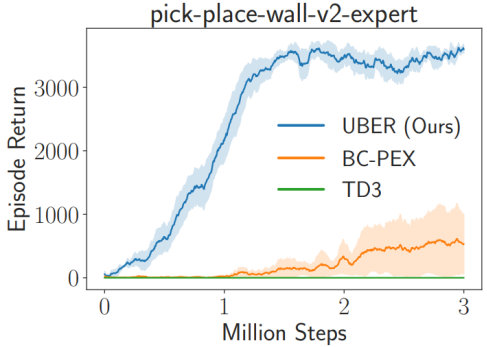
Multi-task: Meta-world

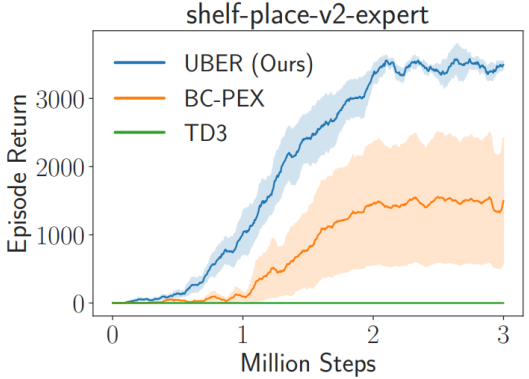
- Source: Push, Reach, Pick-place
- Target: Hammer, Peg-Insert-Side, Push-Wall, Pick-Place-Wall, Push-Back, Shelf-Place

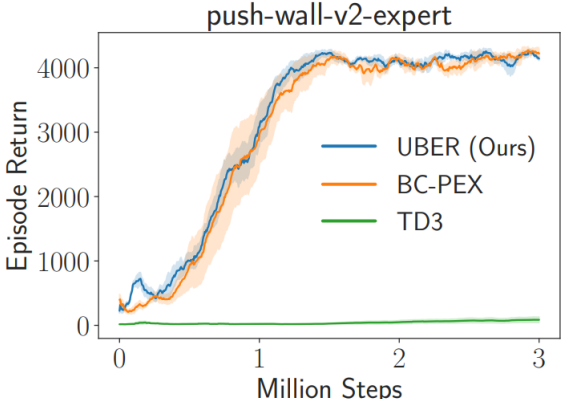


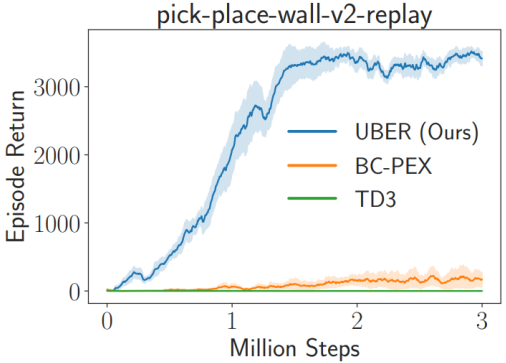


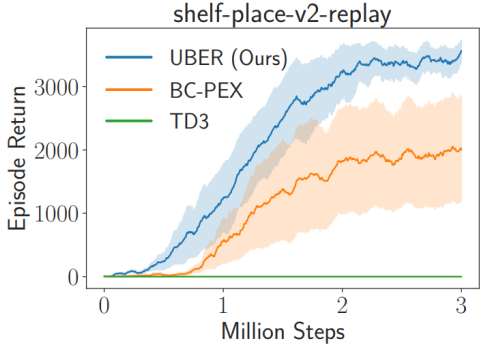
Results

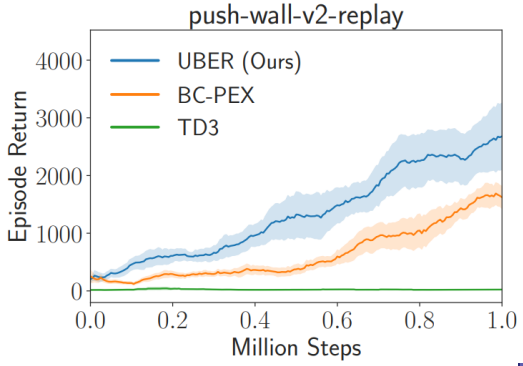

pick-place-wall-v2-expert
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3


shelf-place-v2-expert
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3


push-wall-v2-expert
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3


pick-place-wall-v2-replay
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3


shelf-place-v2-replay
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3


push-wall-v2-replay
Episode Return
Million Steps
UBER (Ours)
BC-PEX
TD3

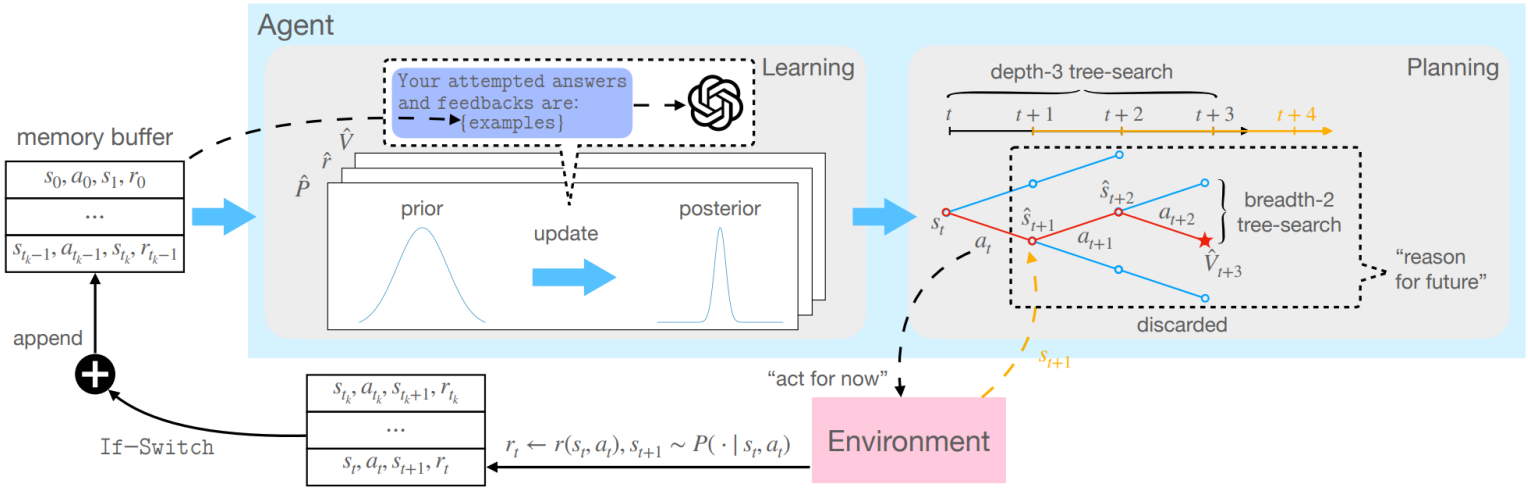
Theoretical Analysis: Coverage

Theorem 4.3. *Assume the reward function $r(s,a)$ admits a RKHS represention $\psi(s,a)$ with $\|\psi(s,a)\|_\infty \leq \kappa$ almost surely. Then with $N = c_0\sqrt{M}\log(18\sqrt{M}\kappa^2/\delta)$ random reward functions $\{r_i\}_{i=1}^N$, the linear combination of the set of random reward functions $\widehat{r}(s,a)$ can approximate the true reward function with error*

$$\mathbb{E}_{(s,a)\sim\rho}[\widehat{r}(s,a) - r(s,a)]^2 \leq c_1 \log^2(18/\delta)/\sqrt{M},$$

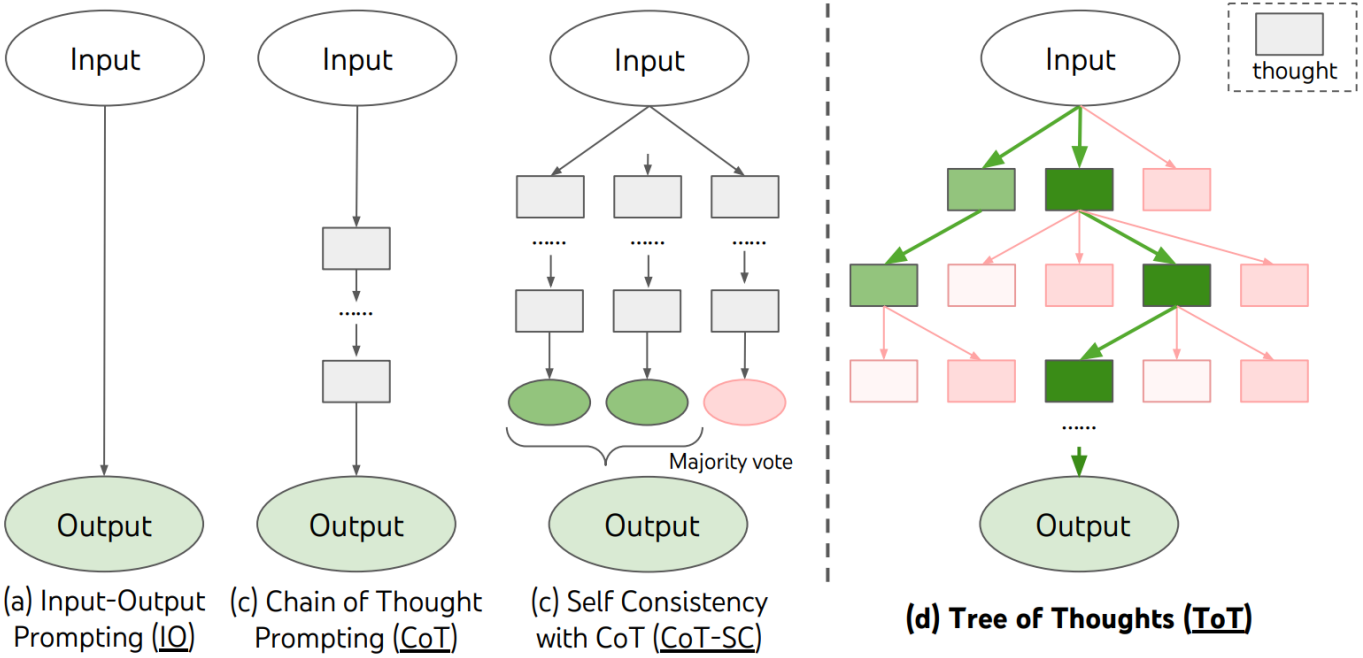
with probability $1-\delta$, where M is the size of the offline dataset $\mathcal{D}$, c_0 and c_1 are universal constants and ρ is the distribution that generates the offline dataset $\mathcal{D}$.

RL with LLMs: Autonomous Agents

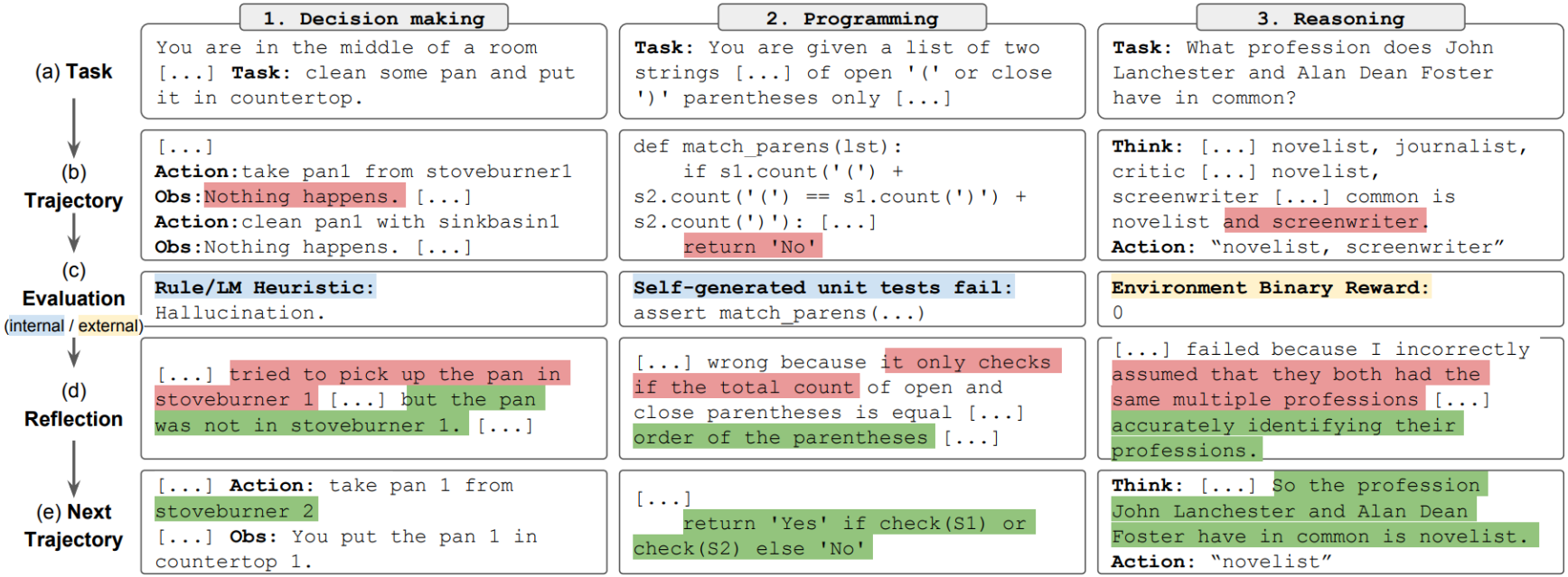


Reason for future, Act for Now [Under Review]

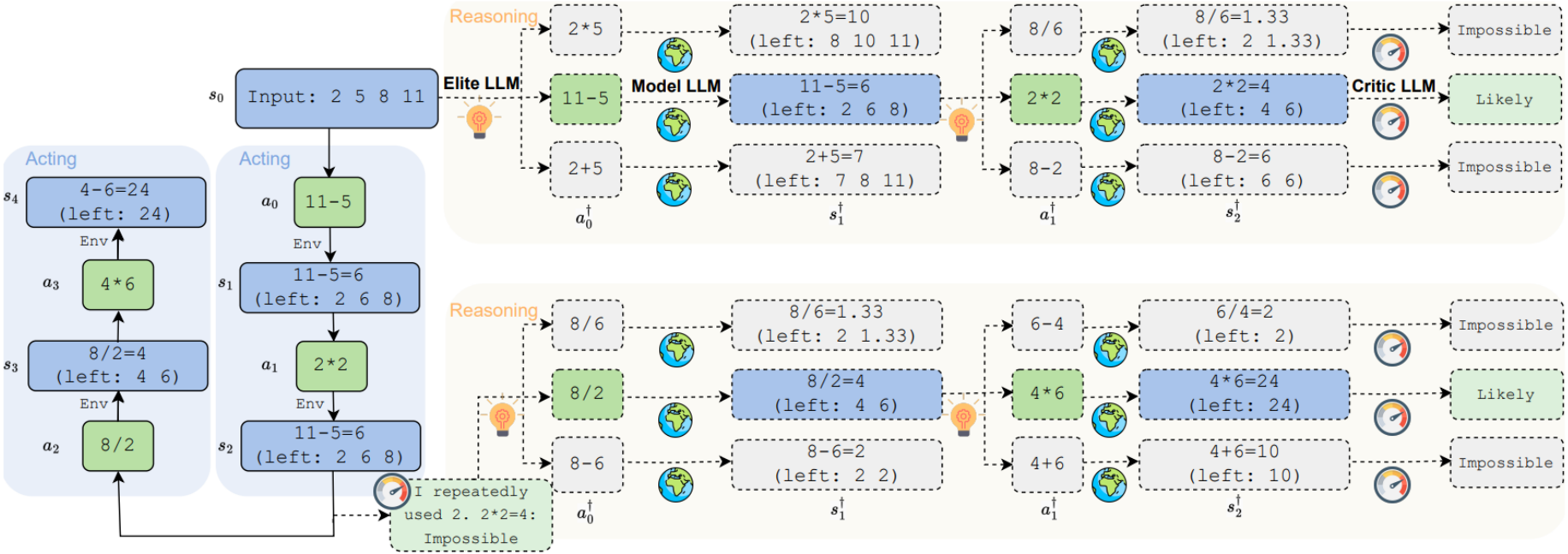
RL with LLMs: Planning



RL with LLMs: Learning



Game of 24


Reasoning
Elite LLM
Model LLM
Critic LLM
Input: 2 5 8 11
2*5
11-5
2+5
2*5=10 (left: 8 10 11)
11-5=6 (left: 2 6 8)
2+5=7 (left: 7 8 11)
8/6
2*2
8-2
8/6=1.33 (left: 2 1.33)
2*2=4 (left: 4 6)
8-2=6 (left: 6 6)
Impossible
Likely
Impossible
Acting
4-6=24 (left: 24)
Env
4*6
8/2=4 (left: 4 6)
8/2
11-5
11-5=6 (left: 2 6 8)
2*2
11-5=6 (left: 2 6 8)
I repeatedly used 2. 2*2=4: Impossible
Reasoning
8/6
8/2
8-6
8/6=1.33 (left: 2 1.33)
8/2=4 (left: 4 6)
8-6=2 (left: 2 2)
6-4
4*6
4+6
6/4=2 (left: 2)
4*6=24 (left: 24)
4+6=10 (left: 10)
Impossible
Likely
Impossible

RAFA Algorithm

Algorithm 1 Reason for future, act for now (`RAFA`): The LLM version.

input: An LLM learner-planner `LLM-LR-PL`, which aims at generating an optimal trajectory given an initial state and returns the initial action (e.g., Algorithm 2), and a switching condition `If-Switch`.

initialization: Sample the initial state $s_0 \sim \rho$, set $t = 0$, and initialize the memory buffer $\mathcal{D}_0 = \varnothing$.

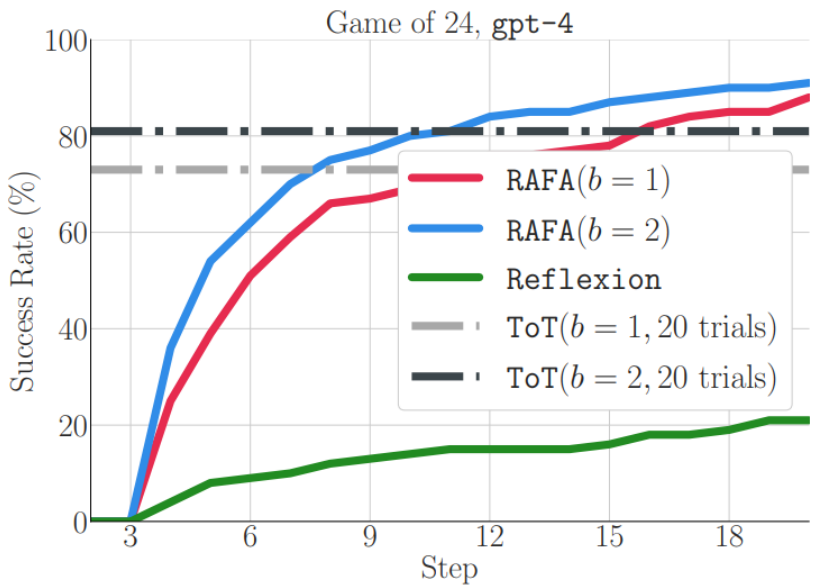
for $k = 0, 1, \ldots,$ **do**
  Set $t_k \leftarrow t$.
  repeat
    Learn and plan given memory $\mathcal{D}_{t_k}$ to get action $a_t \leftarrow$ `LLM-LR-PL`$(\mathcal{D}_{t_k}, s_t)$.("reason for future")
    Execute action a_t to receive reward r_t and state s_{t+1} from environment. ("act for now")
    Update memory $\mathcal{D}_{t+1} \leftarrow \mathcal{D}_t \cup \{(s_t, a_t, s_{t+1}, r_t)\}$.
    Set $t \leftarrow t + 1$.
  until `If-Switch`$(\mathcal{D}_t)$ is `True`. (the switching condition is satisfied)
end for

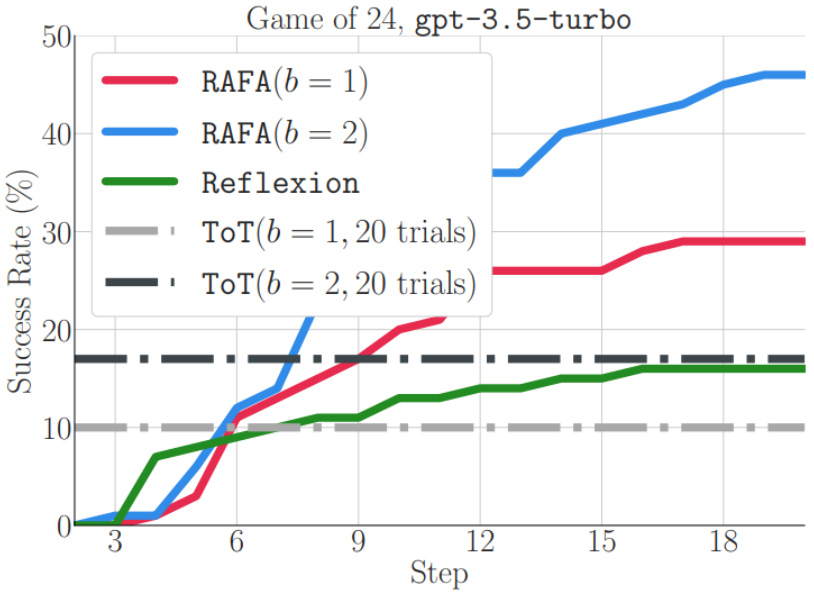
Theorem 4.4 (Bayesian Regret). Under Assumption 4.1, the Bayesian regret of `RAFA` satisfies

$$\mathfrak{R}(T) = \mathcal{O}\left(\frac{\gamma \cdot \sup_{t^\dagger < T} \Gamma_{t^\dagger}(\delta) \cdot \mathbb{E}[\sqrt{H_0 - H_T}]}{1-\gamma} \cdot \sqrt{T} + \frac{\gamma\delta}{(1-\gamma)^2} \cdot T + \epsilon \cdot T + \frac{\gamma \cdot \mathbb{E}[H_0 - H_T]}{(1-\gamma)^2}\right).$$

Experiments

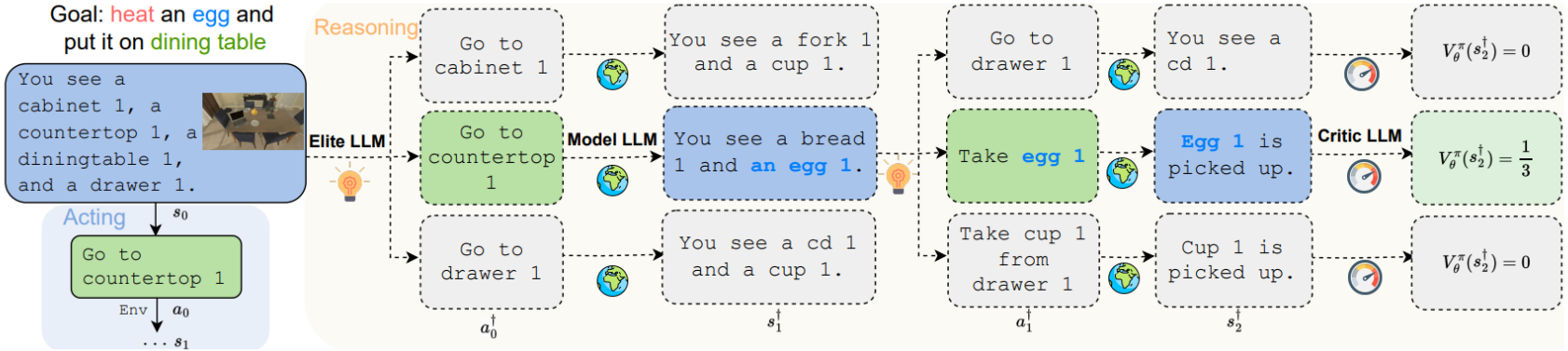
- Game of 24



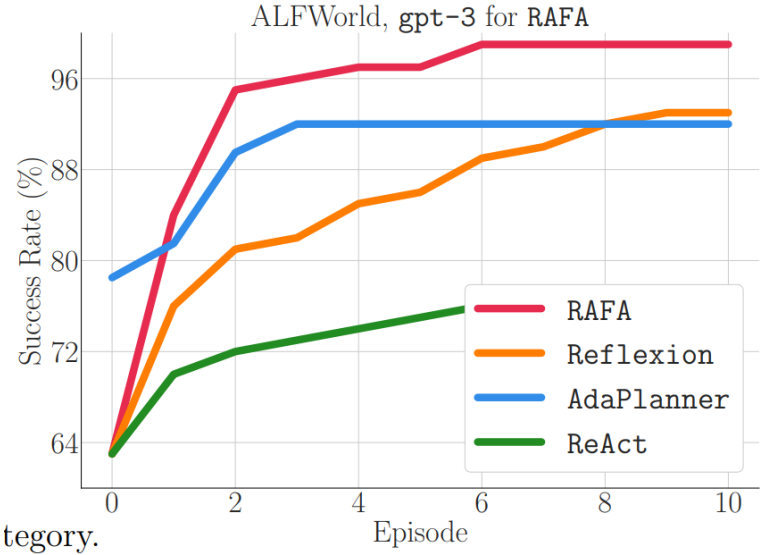


Experiments

- ALFWorld



Experiments



tegory.

Experiments

	Pick	Clean	Heat	Cool	Examine	PickTwo	Total
BUTLER	46.00	39.00	74.00	**100.00**	22.00	24.00	37.00
ReAct	66.67	41.94	91.03	80.95	55.56	35.29	61.94
AdaPlanner	**100.00**	**96.77**	95.65	**100.00**	**100.00**	47.06	91.79
Reflexion	**100.00**	90.32	82.61	90.48	**100.00**	94.12	92.54
RAFA	**100.00**	**96.77**	**100.00**	**100.00**	**100.00**	**100.00**	**99.25**

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Thanks!