Inverse Reinforcement Learning Tool for Minigrid environment

Giulio Bazzanti Niccolò Biondi

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Use Case

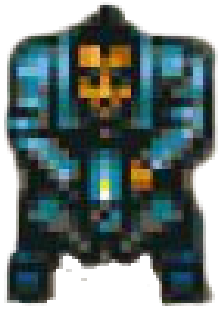
Persona

- Paolo Dibali
- Age 27
- Video Game Designer
- Paolo wants to create his video game

- Non-Player Characters (NPCs) approaches:
  - Handcrafted rules
  - Reinforcement Learning (RL)

Video games and AI

- RL is used in video games to create NPCs
- Two problems:
  - NPCs with super-human abilities
  - NPCs with predictable behavior



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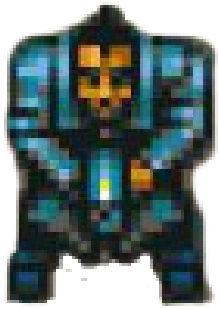
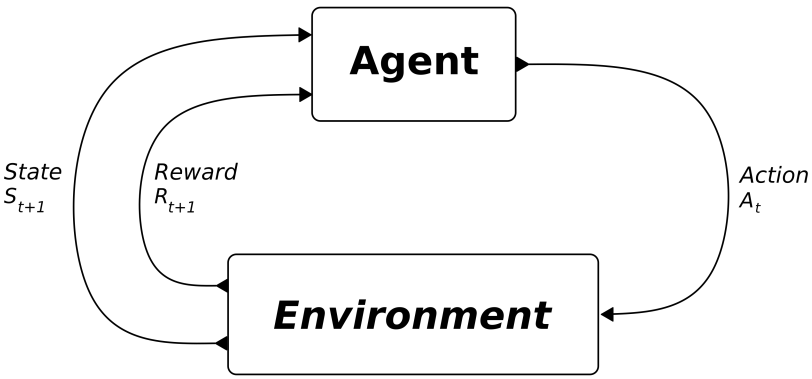
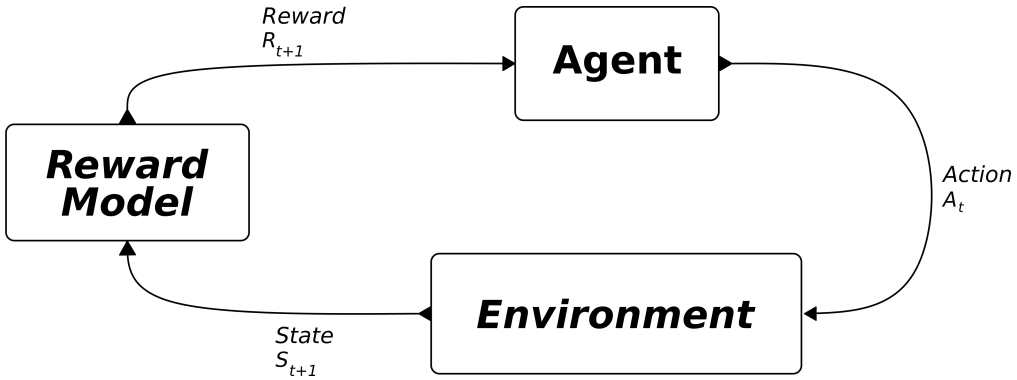


- **Solution:** Paolo can control the agent behavior $\Rightarrow$ IRL

Reinforcement Learning vs Inverse Reinforcement Learning

- RL agent takes environments rewards
- IRL agent receives rewards from a Reward Model

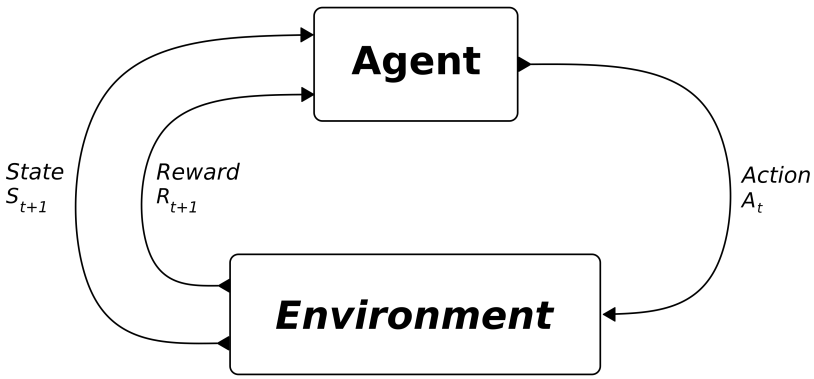


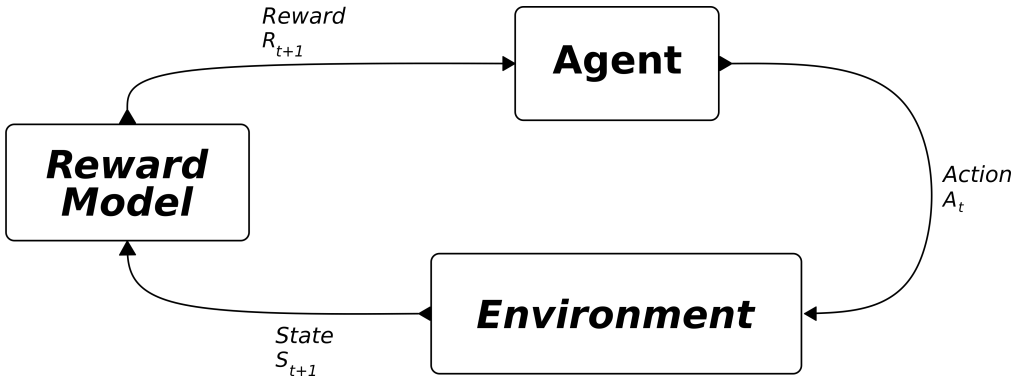


Reinforcement Learning vs Inverse Reinforcement Learning

- RL agent takes environments rewards
- The agent learns the behavior through trial-and-error mechanism

- IRL agent receives rewards from a Reward Model
- The user controls the agent behavior with preference feedback





Proposed Method

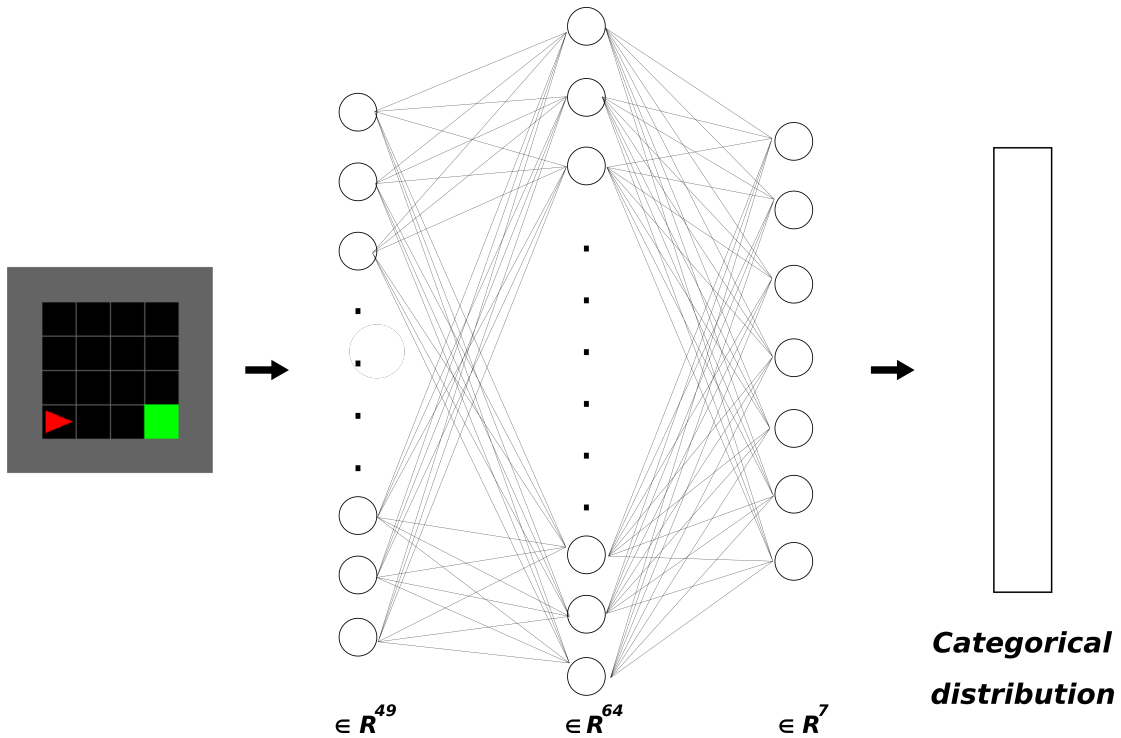
Proposed method

Algorithm 1 Training Protocol

1: Run the policy in the environment and store "initial trajectories".
2: The annotator annotated all the "initial clips" and create the annotation buffer.
3: Pretrain the reward model from the annotation buffer.
4: **for** M epochs **do**
5: Train the policy in the environment for N episodes with rewards from the reward model.
6: Sample pairs of clips from the resulting trajectories.
7: The annotator labels the selected pairs and puts them in the annotation buffer.
8: Train the reward model for K batches from the annotation buffer.
9: **end for**

Policy

- The reward is not taken from the environment but from a reward model
- The policy receives the current agent state as input and probabilities of actions as output



Annotator

- The annotator gives preference feedback about pairs of clips
  - (0,1) (1,0) preferred clips
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- Human annotator vs Artificial annotator (*Oracle*)
- All the preferences are stored in the Annotation Buffer

Reward Model

- The Reward Model has to emulate the annotator labels
- It is trained to minimize the cross-entropy loss between predictions and labels

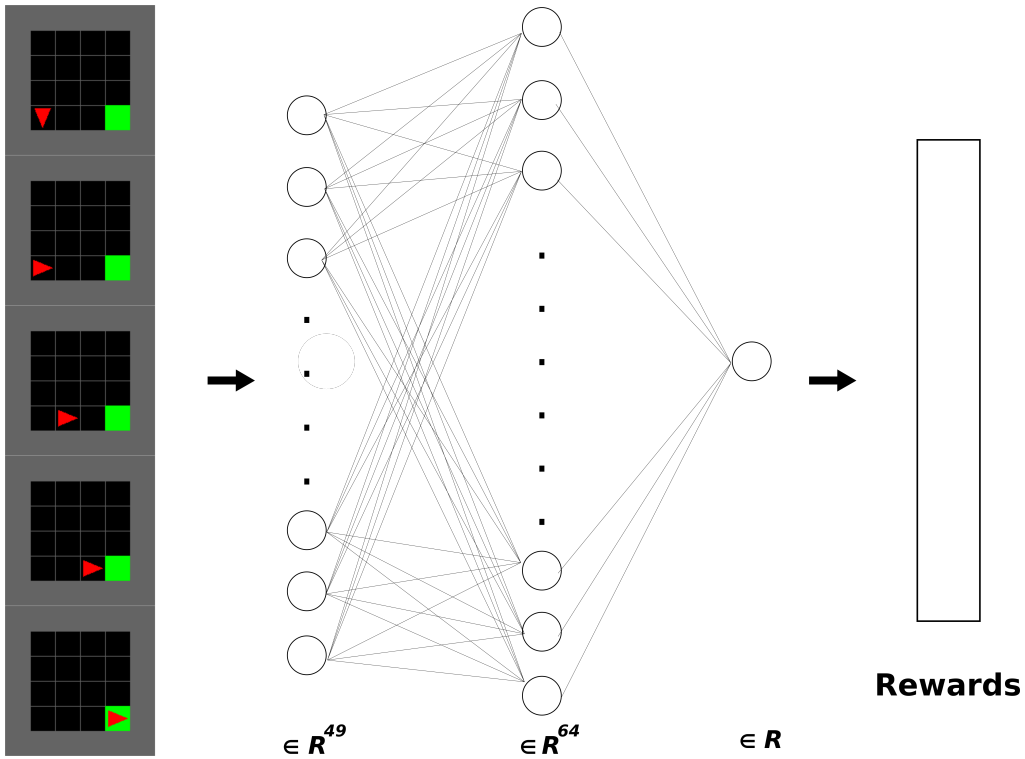
$$loss(\hat{r}) = -\sum_{(\sigma^1,\sigma^2,\mu)\in A} \mu(1) log(\hat{P}[\sigma^1 \succ \sigma^2]) + \mu(2) log(\hat{P}[\sigma^2 \succ \sigma^1])$$

- where

$$\hat{P}[\sigma^1 \succ \sigma^2] = \frac{exp(\sum_{o\in\sigma^1} \hat{r}(o))}{exp(\sum_{o\in\sigma^1} \hat{r}(o) + \sum_{o\in\sigma^2} \hat{r}(o))}$$

Reward Model

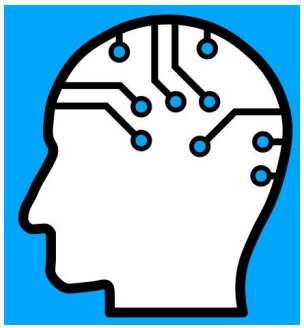
- The Reward Model predicts a list of rewards from a clip

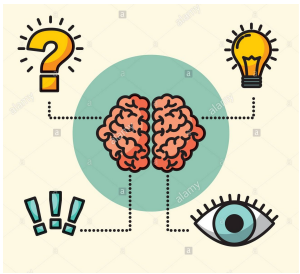


IRL Tool

Motivations

- The user is not a RL (or IRL) expert

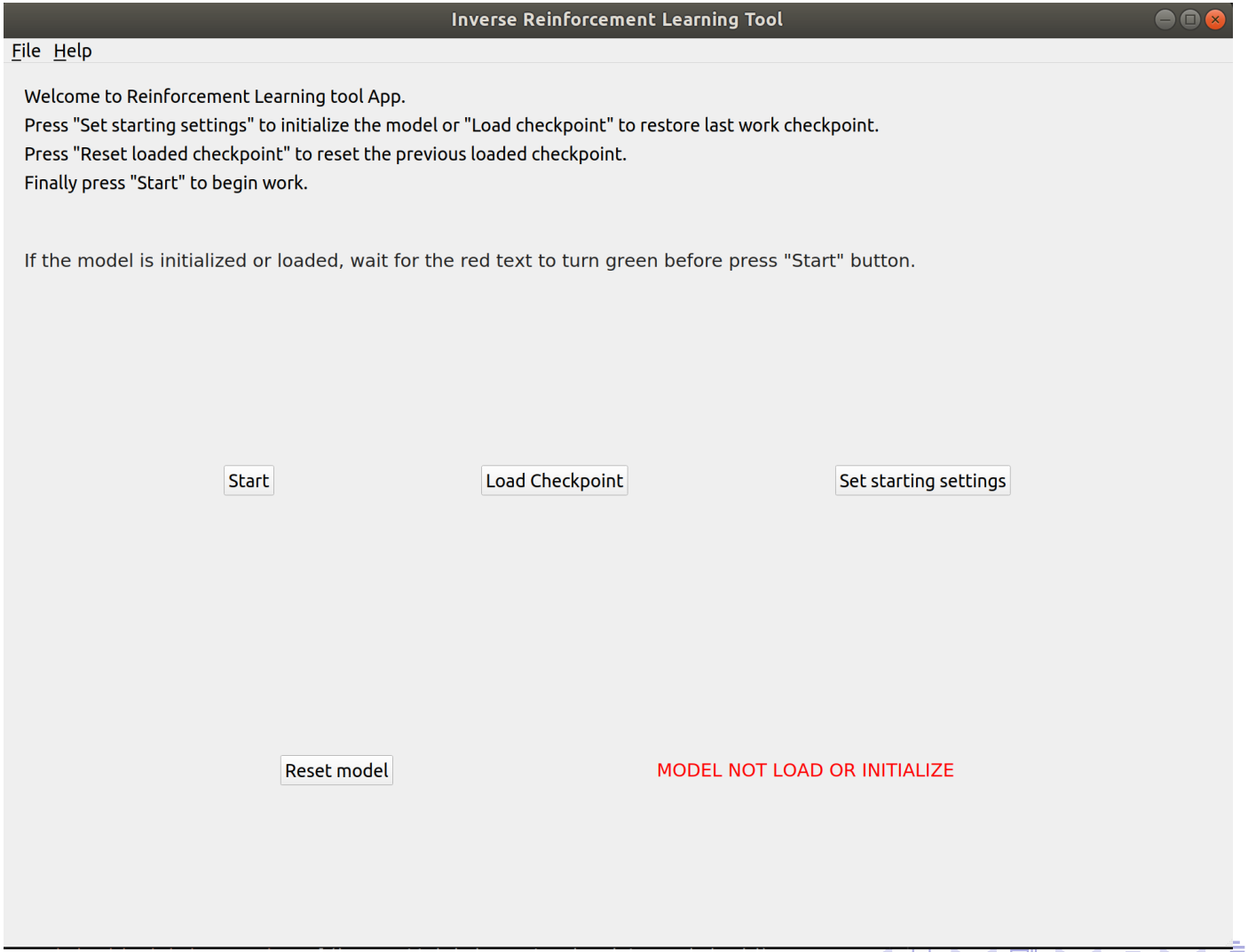




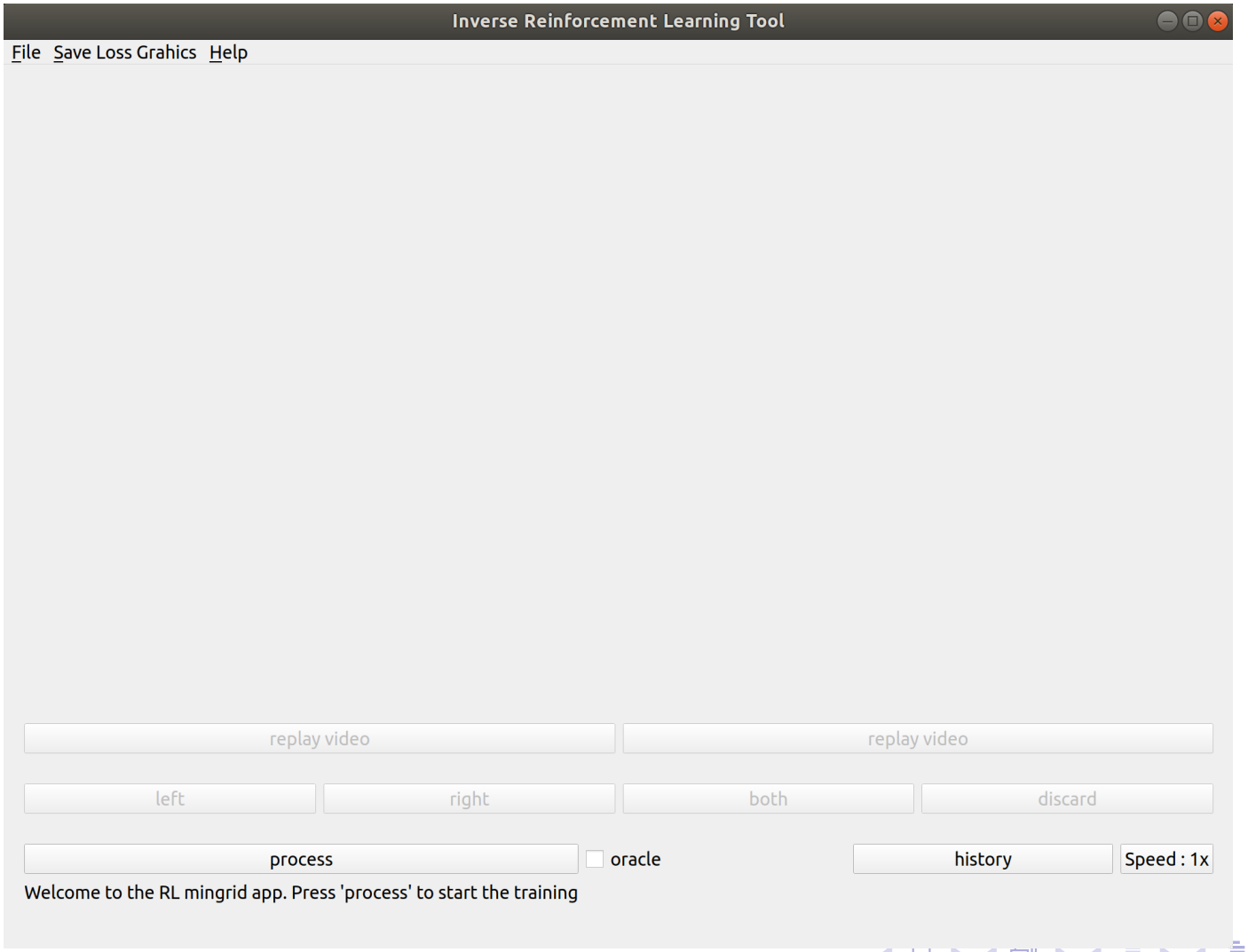
- Simplify the agent behavior understanding

- Better user experience

Set Up Window



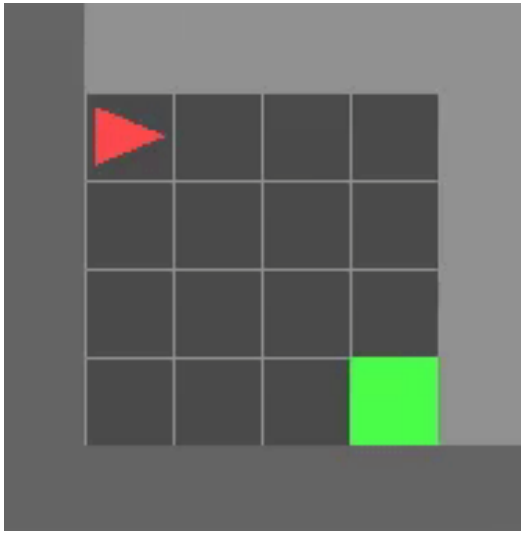
Training iteration



Experimental Results

MiniGrid Environment

- 6x6 Empty MiniGrid environment for experiments
- Optimal trajectory achieved with RL



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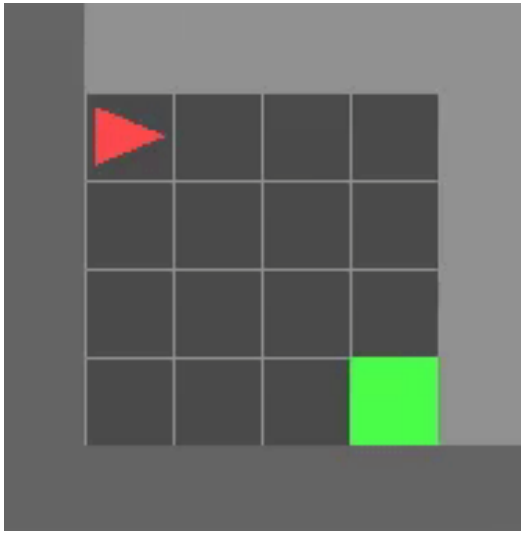
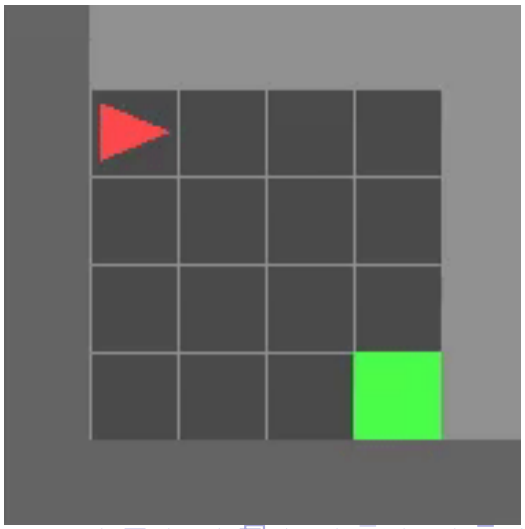


- Sub-optimal trajectory forced with IRL
- The user controls the agent behaviour



Tuning the components

- Policy
  - the agent has to reach easily the environment goal $\Rightarrow$ episode length 150
  - no negative goal reward or big values range $\Rightarrow$ standard deviation 0.5

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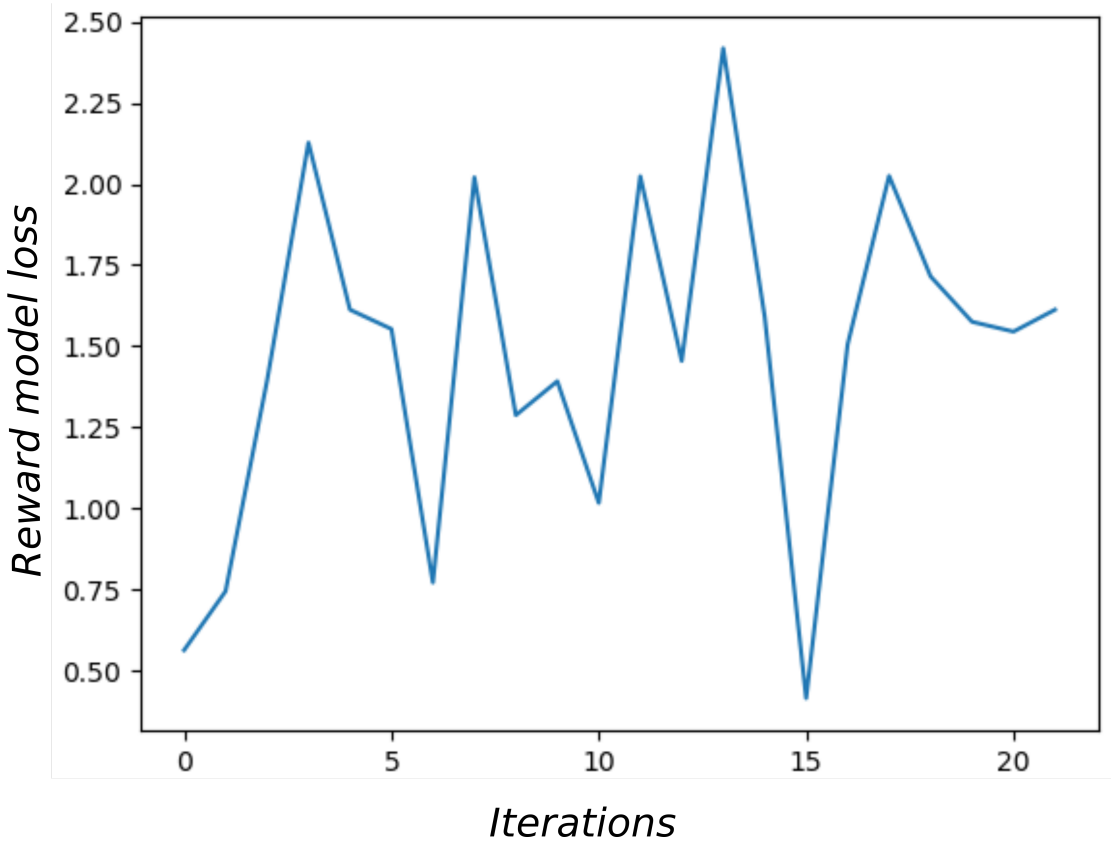
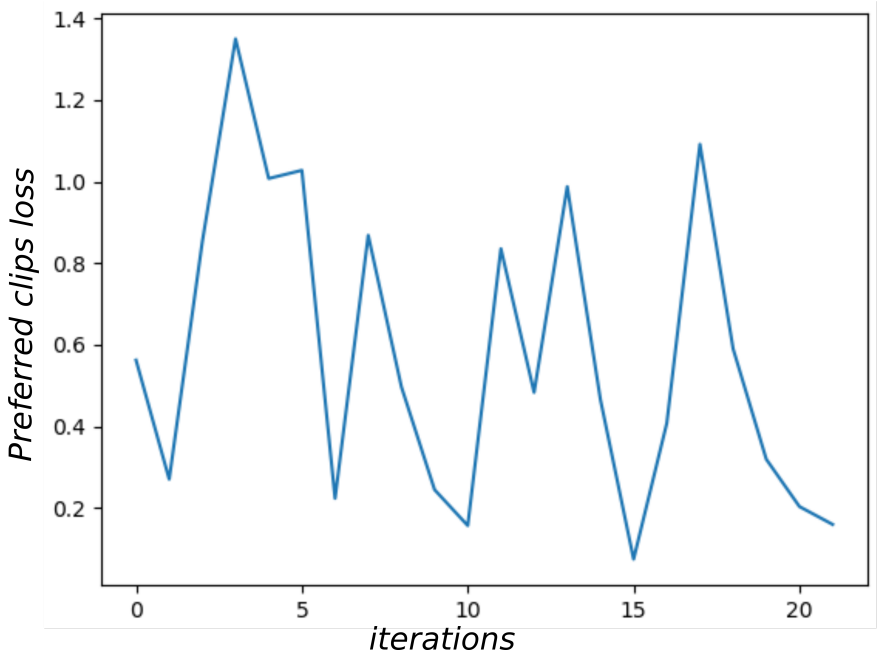
  - no negative goal reward or big values range $\Rightarrow$ standard deviation 0.5
- Annotator
  - sparse vs dense Oracle
- Reward Model
  - variable K batch
  - early stopping

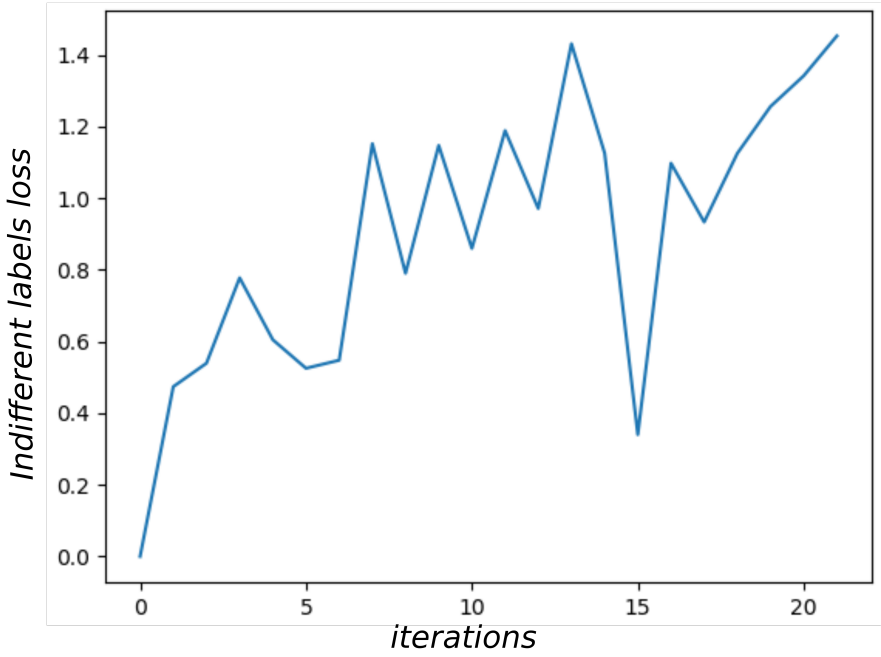
Reward Model Loss

- The reward model loss grows during the training protocol.





- Small contribution to total loss
- Same range during all the training



- Big contribution to total loss
- The number of those preferences make the loss grow

Conclusions

Conclusions and Future Works

- For now . . .
  - A not-expert user can build an IRL system
  - The agent learns sub-optimal trajectory
  - Better NPCs creation
- . . . then
  - More complex environment to increase IRL benefits
  - Process environment images with agent states (with CNN and/or LSTM)

Thanks for the attention