
Inverse Reinforcement Learning

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Overview

What is Reinforcement Learning?

Inverse Reinforcement Learning

Algorithms and Experiments

IRL in Finite Spaces

- 5x5 Grid World

IRL in Large Spaces

- Mountain Car

IRL from Sampled Trajectories

- Continuous Grid World

Conclusion

What is Reinforcement Learning?

Reinforcement Learning

- Definition:
 - Reinforcement learning involves learning what actions to take in different situations to maximize a numerical reward signal.
 - Key Characteristics:
 - Trial-and-Error Search:
 - The learner discovers optimal actions through experimentation rather than being explicitly told what to do.
 - Delayed Reward:
 - Actions may influence not only immediate rewards but also subsequent situations, leading to delayed rewards.
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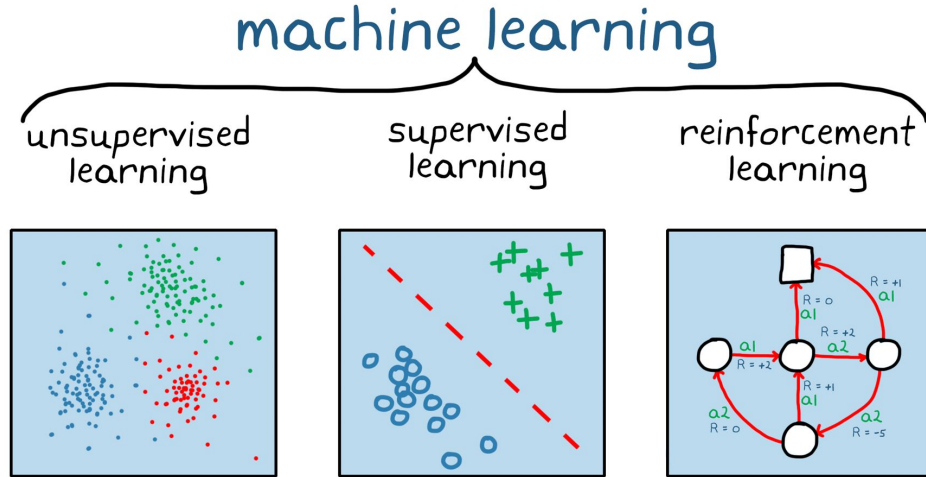
What is Reinforcement Learning?

Reinforcement Learning

- Some Challenges faced:
 - Complex Interactions:
 - Actions may have a cascading effect on future situations, making the learning process intricate.
 - Dynamic Environments:
 - The challenge of adapting to changing circumstances where the consequences of actions evolve over time.
 - Importance:
 - Reinforcement learning is crucial in scenarios where explicit guidance is unavailable, and the agent must learn through interaction.
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What is Reinforcement Learning?

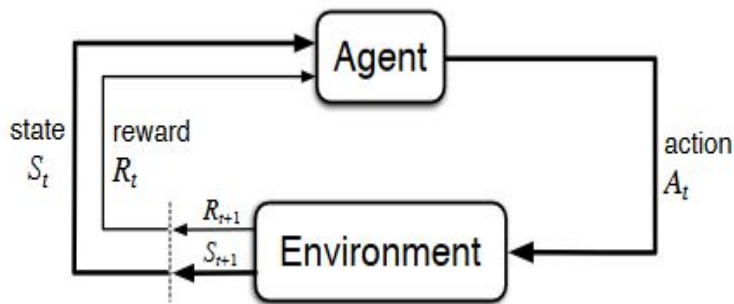
Reinforcement Learning



What is Reinforcement Learning?

Reinforcement Learning

- Computational approach to understanding and automating goal-directed learning and decision making.
- Learning by an agent from direct interaction with its environment (no supervisor)
- We use Markov Decision Processes (MDPs) to formulate the problem of learning.



Components of an RL Agent

Policy

- Agent's Behavior Function
- The policy serves as the agent's guide, determining its behavior by mapping states to actions.
- Types:
 - Deterministic Policy: The agent chooses actions directly based on states
$$a = \pi(s)$$
 - Stochastic Policy: The probability of taking an action a in state s is given by

$$\pi(a|s) = \mathbb{P}[A_t = a | S_t = s]$$

Components of an RL Agent

Value Function

- Evaluation of States and Actions
- The value function assesses the desirability of states and actions, guiding decision-making.
- Used to estimate the expected future rewards, influencing action selection.
- Mathematical Representation:

$$v_{\pi}(s) = \mathbb{E}_{\pi} [R_{t+1} + \gamma R_{t+2} + \gamma^2 R_{t+3} + \dots \mid S_t = s]$$

Components of an RL Agent

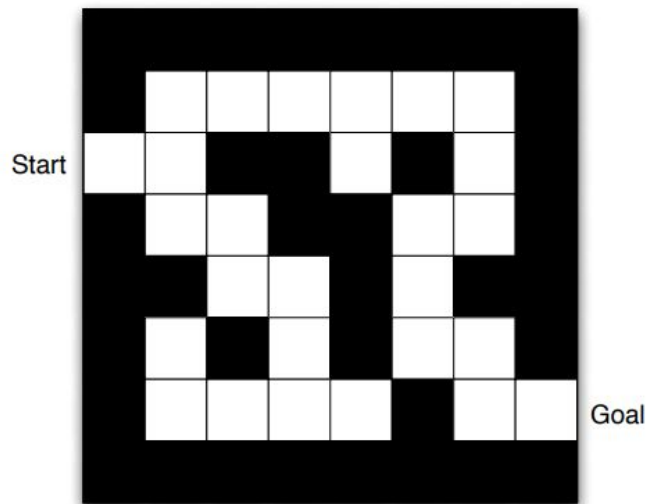
Model of the Environment

- Agent's Representation of the Environment
- The model predicts how the environment will respond to the agent's actions.
- Components:
 - Transition Model (P): Predicts the probability of reaching the next state given the current state and action.
 - Reward Model (R): Predicts the immediate reward expected from a specific action in the current state.

$$\mathcal{P}_{ss'}^a = \mathbb{P}[S_{t+1} = s' \mid S_t = s, A_t = a]$$

$$\mathcal{R}_s^a = \mathbb{E}[R_{t+1} \mid S_t = s, A_t = a]$$

Components of an RL Agent



Rewards: -1 per time-step

Actions: N, E, S, W

States: Agent's location



Goal



Goal

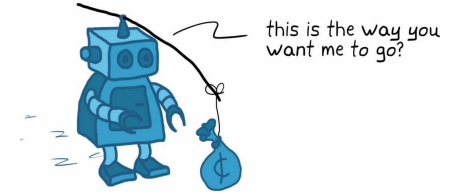


Goal

Reward

reward = function (state, action)

scalar representing "goodness"



reward



Sparse Reward

10 meters



reward



reward



reward



reward



reward



reward



10 meters

Reward Shaping

A Challenge faced by RL

- Given states, actions, sometimes a model of the environment and a reward function, the objective is to learn an optimal policy. It is often easier to specify the reward function than to directly specify the value function (and/or optimal policy)
 - However, in some problems even the reward function is frequently difficult to specify manually.
 - An example is the task of 'driving well'.
-

Inverse Reinforcement Learning

What is Inverse Reinforcement Learning?

- The reverse problem of Reinforcement Learning.
- Reconstruct the reward function by observing an agent (expert) act out under an optimal policy.
- Relevant due to the fact that reward function has to be manually tweaked multiple times in a RL problem and determining the exact reward function is not trivial.



Inverse Reinforcement Learning

Definition

- The problem of deriving a reward function from observed behavior is referred to as inverse reinforcement learning (Ng & Russell, 2000).

Given 1) measurements of an agent's behavior over time, in a variety of circumstances, 2) if needed, measurements of the sensory inputs to that agent; 3) if available, a model of the environment.

Determine the reward function being optimized.

Inverse Reinforcement Learning

RL

given:

states $\mathbf{s} \in \mathcal{S}$, actions $\mathbf{a} \in \mathcal{A}$

(sometimes) transitions $p(\mathbf{s}'|\mathbf{s}, \mathbf{a})$

reward function $r(\mathbf{s}, \mathbf{a})$

learn $\pi^*(\mathbf{a}|\mathbf{s})$

IRL


given:

states $\mathbf{s} \in \mathcal{S}$, actions $\mathbf{a} \in \mathcal{A}$

(sometimes) transitions $p(\mathbf{s}'|\mathbf{s}, \mathbf{a})$

samples $\{\tau_i\}$ sampled from $\pi^*(\tau)$

learn $r_{\psi}(\mathbf{s}, \mathbf{a})$

 reward parameters

...and then use it to learn $\pi^*(\mathbf{a}|\mathbf{s})$

Motivation for Inverse RL

Better Reward Functions

- In some problems, a predefined reward function is not given, and determining an appropriate one is challenging without relying on intuition.
 - This requirement to specify a reward function in advance restricts the potential applications of Reinforcement Learning (RL).
 - Inverse Reinforcement Learning (IRL) addresses this limitation by offering a method to obtain a suitable numerical reward function.
 - While access to an optimal policy is necessary, these demonstrations are typically easily obtainable in practical scenarios from experts.
-

Motivation for Inverse RL

Better Transferability

- A reward function serves as a reflection of an agent's preferences and is transferable to another agent.
 - When the specifications of a second agent only slightly differ from the first one, the learned reward function becomes a foundation for the second agent.
 - However, this advantageous transferability does not extend to optimal policies. For instance, if the second agent has a larger state space while maintaining the same dynamics as the first one, the optimal policy for the first agent does not provide insights into what the optimal policy for the second agent would be.
-

Motivation for Inverse RL

Objectives of Inverse RL

- Application of reinforcement learning and related methods as computational models for animal and human learning - we must consider the reward function as an unknown to be ascertained through empirical investigation.
- Learn from 'expert' agents (like humans) - recover the reward function instead of directly learning the policy.

“The reward function, rather than the policy, is the most succinct, robust, and transferable definition of the task”

Applications of Inverse RL

Apprenticeship Learning

- Definition: Apprenticeship learning involves transferring the learned reward function from an expert's Markov Decision Process (MDP) to another model that describes the learning agent.
 - Purpose: Enables the learning agent to accomplish tasks similarly to the expert, addressing challenges like different body types or capabilities.
-

Applications of Inverse RL

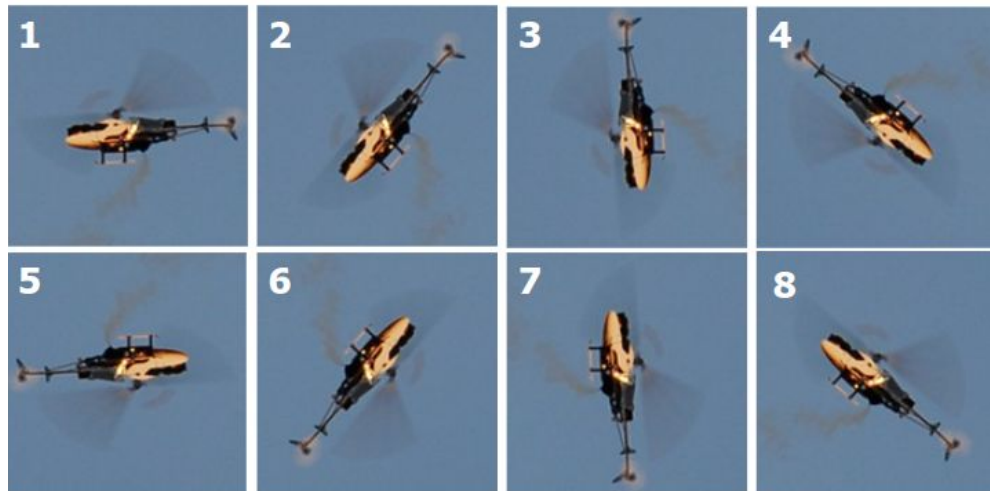
Apprenticeship Learning

- Examples:
 - Grasping techniques for sorting objects (Bogert et. al. [11]).
 - Driving a simulated car or sailing a simulated boat (Abbeel and Ng [3], Neu [40]).
 - Flying a helicopter (Abbeel et. al. [1]).
 - Robot path planning that mimics teachers (Ratliff et. al. [48]).
 - Grasping unknown objects by their handle, playing children's motor games, and playing table tennis (Boularias et. al. [14, 13], Muelling et. al. [36]).
-

Applications of Inverse RL



Pieter Abbeel and Andrew Y. Ng



Pieter Abbeel, Adam Coates, Morgan Quigley and Andrew Y. Ng

Applications of Inverse RL



Applications of Inverse RL

Prediction of Expert Motion

- IRL completes the Markov Decision Process with Rewards (MDP/R) model of an expert, offering a valuable application in predicting expert actions in unobserved states.
 - Use Cases:
 - Determining future locations of patrolling robots for avoidance (Bogert and Doshi [9, 10]).
 - Predicting expert behavior in new scenarios using transferred reward functions (Vogel et. al. [58], Shimosaka et. al. [52], Kitani et. al. [26], Ratliff et. al. [48], Kim and Pineau [24]).
 - Examples include optimizing fuel efficiency in a hybrid car and predicting driver behavior on residential roads and predicting the future path of humans so that, for example, path planning by a robot can avoid collisions with them.
-

Applications of Inverse RL

Other

- IRL finds applications in various domains beyond apprenticeship learning and prediction of expert motion.
 - Examples:
 - Learning expert behavior for interaction in spoken dialog where the rules of taking turns speaking are learned. (Kim et. al. [25]).
 - Completing models when important decision-making data is missing, such as inferring car routes from sparse GPS point-measurements (Osogami and Raymond [45]).
-

Applications of Inverse RL

Other

- IRL also finds applications in other domains such as
 - Natural Language Processing for Text Generation (eg: Shi et al.)
 - Inverse Reinforcement Learning for Architecture Search to optimize neural network structures (eg: Minghao Guo et al.)
 - Healthcare systems
 - Recommender systems
-

Methods used in IRL

Methods

- To obtain the unique solution in IRL, many studies have proposed additional objective functions to be optimized, such as **margin between the optimal policy and others** [Ng and Russell, 2000, Abbeel and Ng, 2004, Ratliff et al., 2006b,a, 2009, Silver et al., 2010] and to **maximize the entropy** [Ziebart et al., 2008, Ziebart, 2010, Kitani et al., 2012, Shiarlis et al., 2016]
 - Other IRL methods include **Bayesian IRL** [Ramachandran and Amir, 2007], **Guided Cost Learning**, **Generative Adversarial Imitation Learning (GAIL)** [Ho and Ermon, 2016] etc..
-

Algorithms and Experiments (Ng & Russel, 2000)

IRL in Finite Spaces

I. IRL in Finite Spaces

- The state space is finite, the model is known, and the complete policy is observed.
- Components (MDP):
 - **Finite State Space (S)**: The set of possible states is finite.
 - **Actions (A)**: A set of k actions, denoted as $A=\{a_1,\dots,a_k\}$.
 - **Transition Probabilities (P_{sa})**: The probabilities of transitioning from one state to another given an action.
 - **Discount Factor (γ)**: A discount factor influencing the importance of future rewards.
 - **Policy (π)**: An observed policy for decision-making.
- Objective:

The goal is to find a **set of possible reward functions (R)** such that the given policy π is an optimal policy within the MDP $(S,A,\{P_{sa}\},\gamma,R)$.

I. IRL in Finite Spaces

- The characterization of the set of all reward functions for which a given policy is optimal in the context of Inverse Reinforcement Learning (IRL) in finite state spaces is given by

Theorem 3 *Let a finite state space S , a set of actions $A = \{a_1, \dots, a_k\}$, transition probability matrices $\{P_a\}$, and a discount factor $\gamma \in (0, 1)$ be given. Then the policy π given by $\pi(s) \equiv a_1$ is optimal if and only if, for all $a = a_2, \dots, a_k$, the reward R satisfies*

$$(P_{a_1} - P_a)(I - \gamma P_{a_1})^{-1}R \succeq 0 \quad (4)$$

I. IRL in Finite Spaces

Theorem 3 *Let a finite state space S , a set of actions $A = \{a_1, \dots, a_k\}$, transition probability matrices $\{P_a\}$, and a discount factor $\gamma \in (0, 1)$ be given. Then the policy π given by $\pi(s) \equiv a_1$ is optimal if and only if, for all $a = a_2, \dots, a_k$, the reward R satisfies*

$$(P_{a_1} - P_a)(I - \gamma P_{a_1})^{-1}R \succeq 0 \quad (4)$$

- This theorem provides an optimality condition for a policy to be optimal in terms of the reward function.
 - The term $(P_{a_1} - P_a)$ reflects the difference in the transition probabilities when taking action a_1 compared to the other actions a .
 - $(I - \gamma P_{a_1})^{-1}$: This part represents the inverse of the matrix resulting from the discounted transition probabilities when taking action a_1 .
 - The inequality indicates that the resulting vector R should be a non-negative vector.
-

I. IRL in Finite Spaces

- It is derived from the Bellman (1,2) and Bellman Optimality (3) equations.

$$V^\pi(s) = R(s) + \gamma \sum_{s'} P_{s\pi(s)}(s') V^\pi(s') \quad (1)$$

$$Q^\pi(s, a) = R(s) + \gamma \sum_{s'} P_{sa}(s') V^\pi(s') \quad (2)$$

$$\pi(s) \in \arg \max_{a \in A} Q^\pi(s, a) \quad (3)$$

Proof. Since $\pi(s) \equiv a_1$, Equation (1) may be written $\mathbf{V}^\pi = \mathbf{R} + \gamma \mathbf{P}_{a_1} \mathbf{V}^\pi$. Thus,¹

$$\mathbf{V}^\pi = (\mathbf{I} - \gamma \mathbf{P}_{a_1})^{-1} \mathbf{R} \quad (5)$$

Substituting Equation (2) into (3) from Theorem 2, we see that $\pi \equiv a_1$ is optimal if and only if

$$a_1 \equiv \pi(s) \in \arg \max_{a \in A} \sum_{s'} P_{sa}(s') V^\pi(s') \quad \forall s \in S$$

$$\begin{aligned} &\Leftrightarrow \sum_{s'} P_{sa_1}(s') V^\pi(s') \\ &\geq \sum_{s'} P_{sa}(s') V^\pi(s') \quad \forall s \in S, a \in A \end{aligned}$$

$$\Leftrightarrow \mathbf{P}_{a_1} \mathbf{V}^\pi \succeq \mathbf{P}_a \mathbf{V}^\pi \quad \forall a \in A \setminus a_1$$

$$\begin{aligned} &\Leftrightarrow \mathbf{P}_{a_1} (\mathbf{I} - \gamma \mathbf{P}_{a_1})^{-1} \mathbf{R} \\ &\succeq \mathbf{P}_a (\mathbf{I} - \gamma \mathbf{P}_{a_1})^{-1} \mathbf{R} \quad \forall a \in A \setminus a_1 \end{aligned}$$

where the last implication in this derivation used Equation (5). This completes the proof. \square

I. IRL in Finite Spaces

- However, $R=0$ is a solution and there could be multiple solutions that satisfy (4)
- Linear Programming can be used to find feasible point of constraints
- Not all solutions are equally meaningful, and there is a desire to choose between solutions satisfying the given optimality condition.
- The goal is to choose a reward function R that not only makes the given policy $\pi=a_1$ optimal but also favors solutions where any single-step deviation from π is as costly as possible.
- We aim to maximize the sum of differences between the quality of the optimal action and the quality of the next-best action (maximum margin).

$$\sum_{s \in S} \left(Q^\pi(s, a_1) - \max_{a \in A \setminus a_1} Q^\pi(s, a) \right) \quad (6)$$

I. IRL in Finite Spaces

- A penalty term is introduced in the objective function, represented as $-\lambda ||\mathbf{R}||$ to favor solutions with mainly small rewards, assuming that simpler solutions are preferable.
- The adjustable penalty coefficient λ balances the goals of having small reinforcements and maximizing the sum of differences.
- Putting it all together, the optimization problem is formulated as:

$$\begin{aligned} \text{maximize} \quad & \sum_{i=1}^N \min_{a \in \{a_2, \dots, a_k\}} \{(\mathbf{P}_{a_1}(i) - \mathbf{P}_a(i)) \\ & (\mathbf{I} - \gamma \mathbf{P}_{a_1})^{-1} \mathbf{R}\} - \lambda ||\mathbf{R}||_1 \\ \text{s.t.} \quad & (\mathbf{P}_{a_1} - \mathbf{P}_a)(\mathbf{I} - \gamma \mathbf{P}_{a_1})^{-1} \mathbf{R} \succeq 0 \\ & \forall a \in A \setminus a_1 \\ & |\mathbf{R}_i| \leq R_{\max}, \quad i = 1, \dots, N \end{aligned}$$

- This can be solved efficiently as a linear program.
-

5x5 Grid World

Experiment 1: 5x5 Grid World

- 5x5 grid world where the agent starts from the lower-left grid square and aims to reach the upper-right grid square, receiving a reward of 1 upon reaching it.
 - Actions correspond to moving in the four compass directions but are noisy, having a 30% chance of moving in a random direction instead.
 - An optimal policy is known
 - Objective:
 - The inverse reinforcement problem involves recovering the reward structure given the known policy and problem dynamics.
 - Result:
 - Obtained a reward function which closely approximated the true reward
-

Experiment 1: 5x5 Grid World

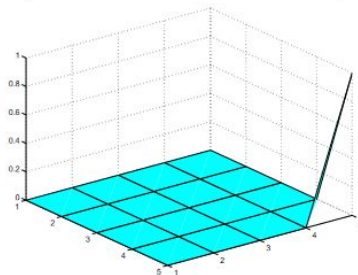
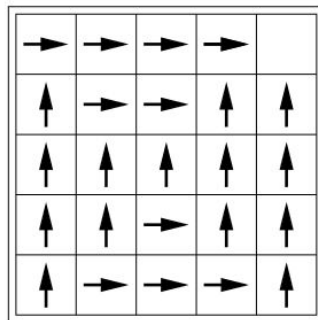


Figure 1. Top: 5x5 grid world with optimal policy. Bottom: True reward function.

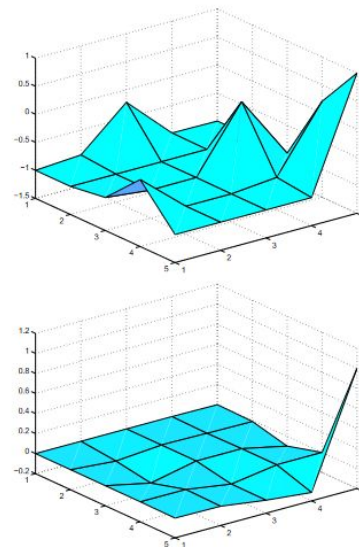
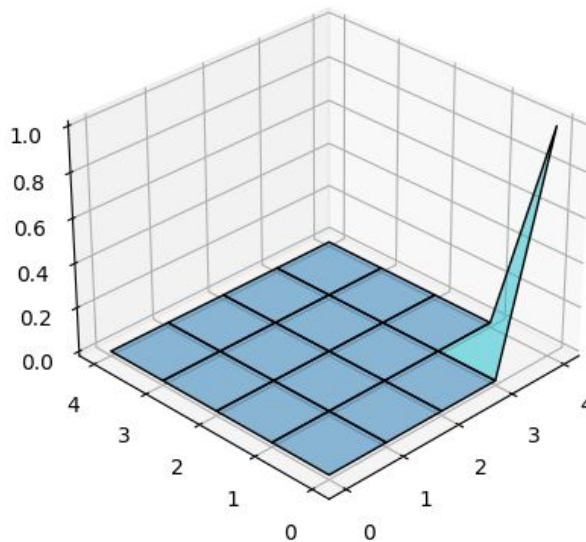


Figure 2. Inverse RL on the 5×5 grid. Top: $\lambda = 0$. Bottom: $\lambda = 1.05$.

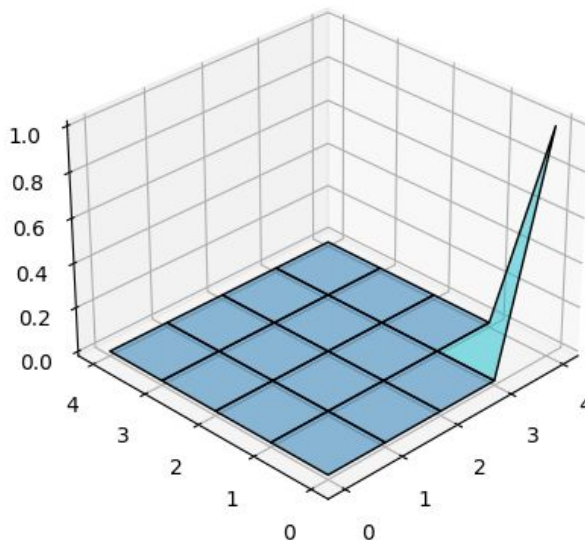
Experiment 1: 5x5 Grid World

True Reward Function



Experiment 1: 5x5 Grid World

True Reward Function

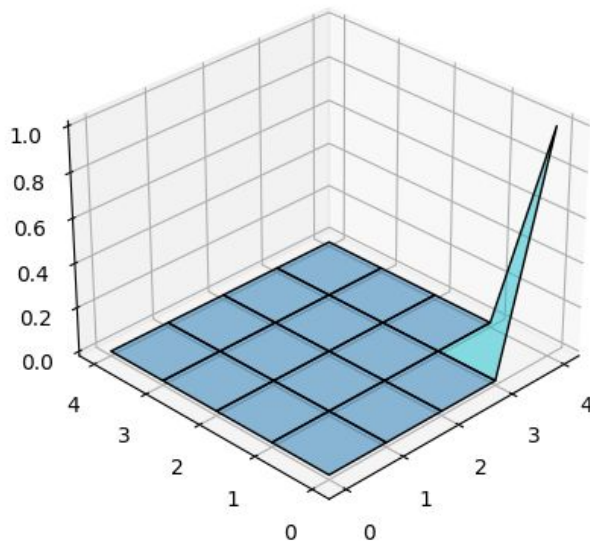


Given Optimal Policy:

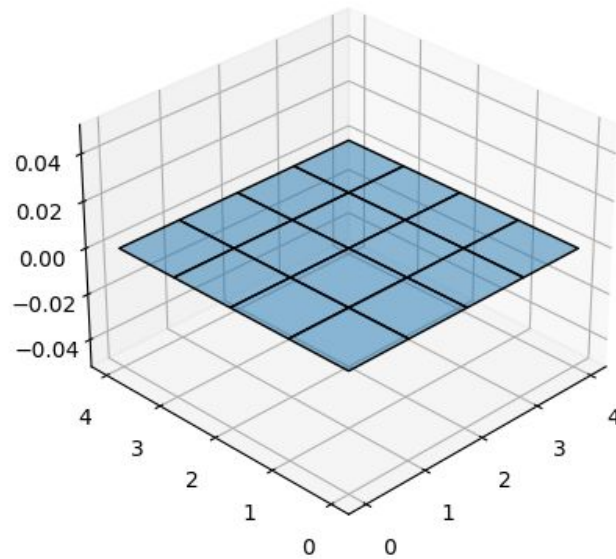
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[ '↑', '→', '→', '↑', '↑' ]  
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Experiment 1: 5x5 Grid World

True Reward Function

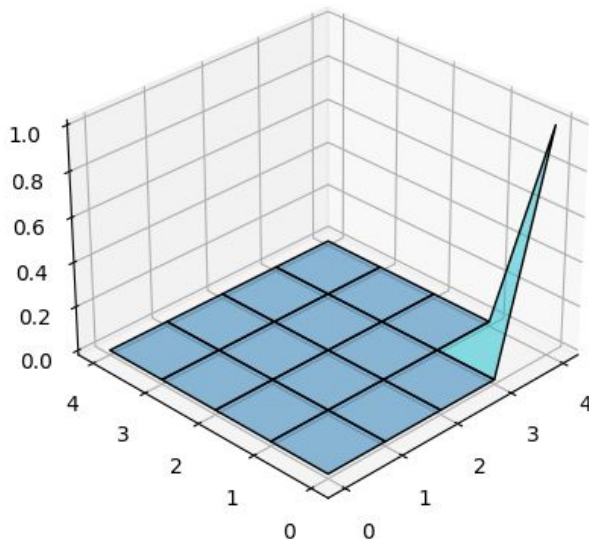


(Without optimization)
Degenerate Solution



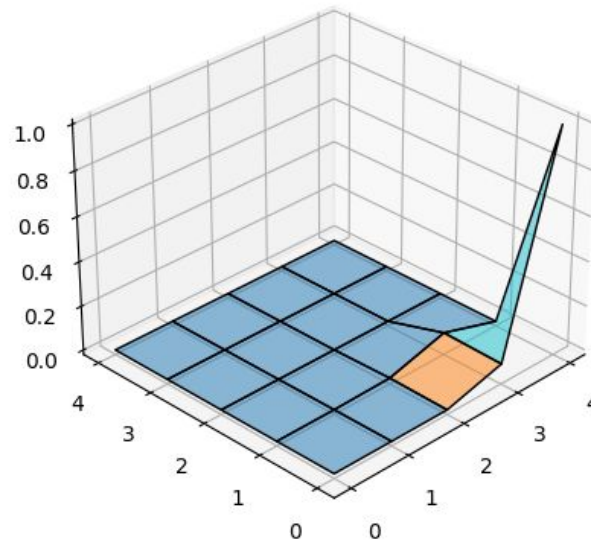
Experiment 1: 5x5 Grid World

True Reward Function



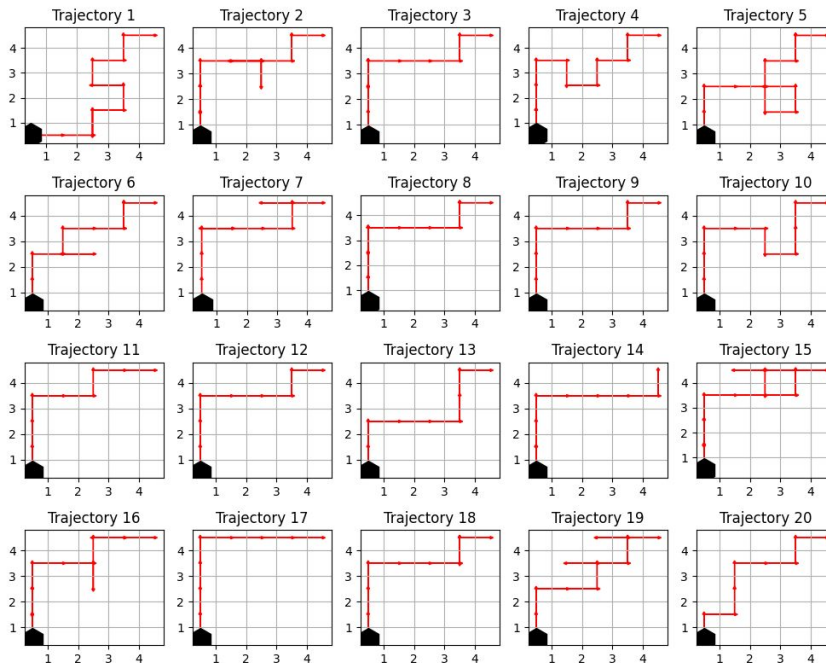
(After optimization)

Inverse RL Reward Function

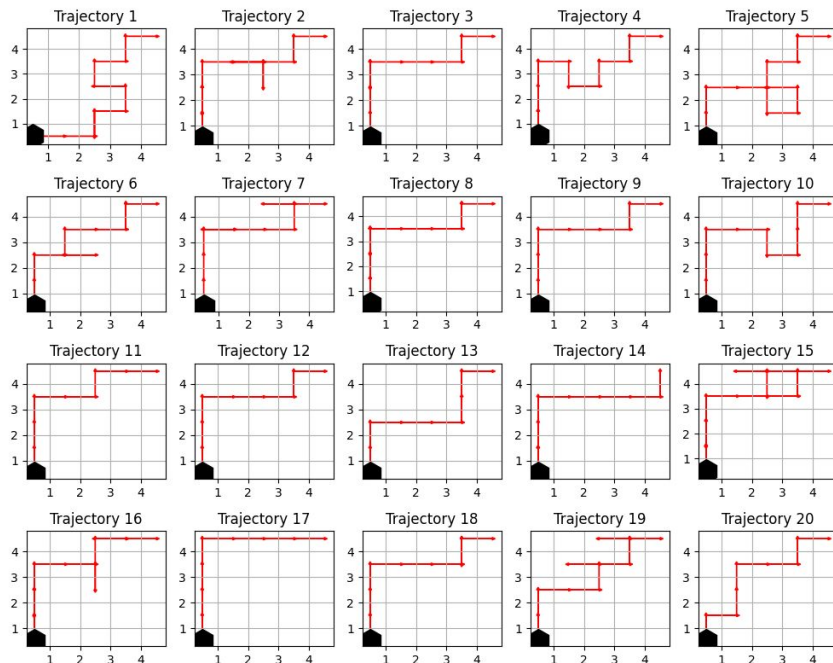


Experiment 1: 5x5 Grid World

Training
Agent
(Expert)



Experiment 1: 5x5 Grid World



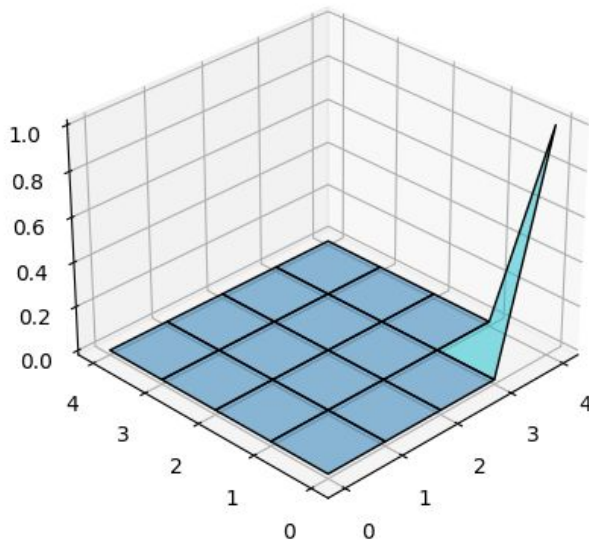
Policy (directions):



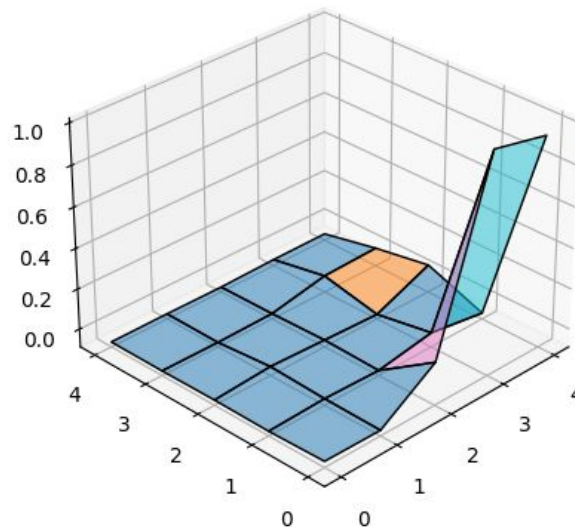
Policy obtained
from expert

Experiment 1: 5x5 Grid World

True Reward Function



Inverse RL Reward Function (from expert)



IRL in Large State Spaces

II. IRL in Large State Spaces

- Infinite-state Markov Decision Processes (MDPs) are considered, specifically with the state space $S = \mathbb{R}^n$
- The reward function R is now a function from S to the real numbers.
- **Linear Function Approximation:**
 - The reward function $R(s)$ is expressed as a linear combination of fixed, known, and bounded basis functions $\phi_1 \dots \phi_d$

$$R(s) = \alpha_1 \phi_1(s) + \alpha_2 \phi_2(s) + \dots + \alpha_d \phi_d(s) \quad (8)$$

- The α s are unknown parameters that need to be 'fit'.
- The value function when R is given by the linear combination is expressed as:

$$V^\pi = \alpha_1 V_1^\pi + \dots + \alpha_d V_d^\pi. \quad (9)$$

II. IRL in Large State Spaces

- The value function when R is given by the linear combination is expressed as:

$$V^\pi = \alpha_1 V_1^\pi + \dots + \alpha_d V_d^\pi. \quad (9)$$

- which gives,

$$\mathbb{E}_{s' \sim P_{sa_1}} [V^\pi(s')] \geq \mathbb{E}_{s' \sim P_{sa}} [V^\pi(s')] \quad (10)$$

The notation $\mathbb{E}_{s' \sim P_{sa}} [V^\pi(s')]$ represents the expected value of the value function $V^\pi(s')$ when transitioning from state s to state s' under action a .

II. IRL in Large State Spaces

- **Sampling for Infinite State Spaces:**
 - Due to the **challenge of having infinitely many constraints**, the formulation is adjusted by sampling a **large but finite subset S_0** of states.
 - The linear constraints are then applied only to this subset of states.
 - **Penalty for Violation:**
 - A penalty term is introduced to handle the **potential issue of not being able to express any reward function** (other than the trivial $R=0$) for which π is optimal due to linear function approximation.
 - The penalty term penalizes violations of the constraints (some constraints are relaxed), and the penalty weight is an adjustable parameter.
-

II. IRL in Large State Spaces

- The final linear programming formulation is as follows:

$$\begin{aligned} & \text{maximize } \sum_{s \in S_0} \min_{a \in \{a_1, \dots, a_k\}} \{ \\ & \quad p(\mathbb{E}_{s' \sim P_{sa_1}} [V^\pi(s')] - \mathbb{E}_{s' \sim P_{sa}} [V^\pi(s')]) \} \\ & \text{s.t. } |\alpha_i| \leq 1, \quad i = 1, \dots, d \end{aligned}$$

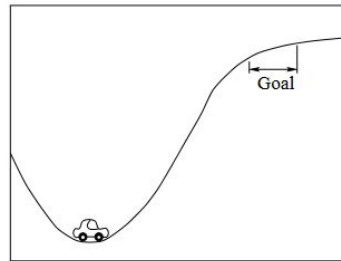
$$\text{where } p(r) = \begin{cases} r & \text{if } r \geq 0 \\ 2r & \text{otherwise} \end{cases}$$

- The objective is to maximize a weighted sum over the sampled states S_0 of the minimum violation of the optimality conditions.
 - The constraints ensure that the coefficients α_i are bounded.
 - The penalty function $p(r)$ penalizes violations, with the penalty weight 2 being an adjustable parameter.
-

Mountain Car

Experiment 2: Mountain Car

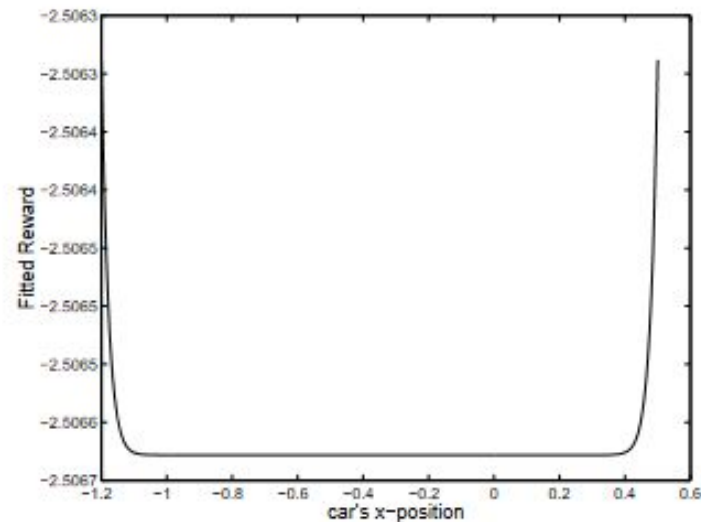
- Utilized the well-known "mountain-car" task.
- True, undiscounted reward is -1 per step until reaching the goal at the top of the hill.
- The state is defined by the car's position and velocity.
- Due to the continuous state space, the version of the algorithm described in Section 4 (Linear Function Approximation in Large State Spaces) was applied.
- The function approximator class for the reward was chosen to be functions of the car's position only, consisting of all linear combinations of 26 evenly spaced Gaussian-shaped basis functions.



Experiment 2: Mountain Car

Experiment 2.1: Original Task:

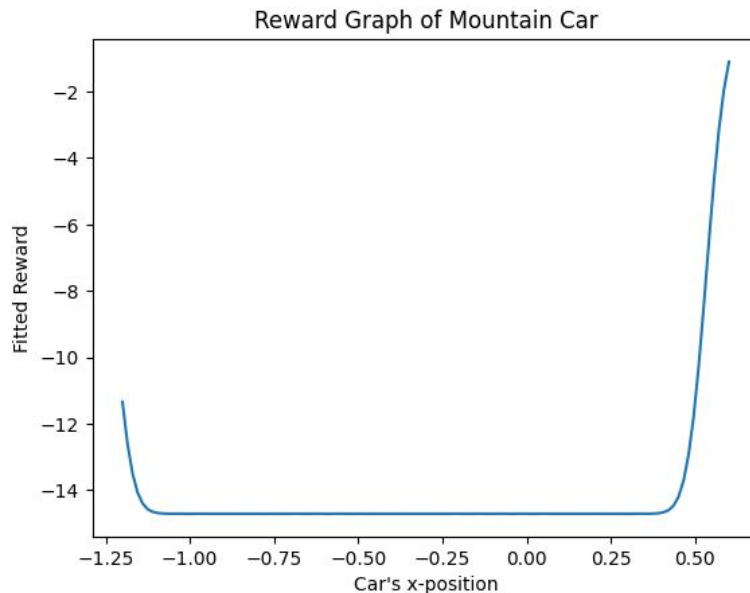
- Provided the optimal policy to the algorithm.
- The solution accurately captures the reward structure.



Experiment 2: Mountain Car

Experiment 2.1: Original Task:

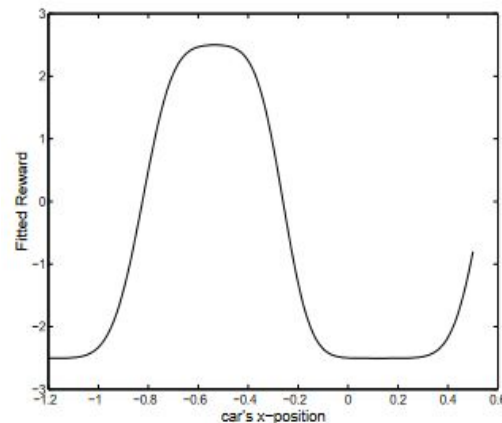
- Provided the optimal policy to the algorithm.
- The solution accurately captures the reward structure.



Experiment 2: Mountain Car

Experiment 2.2: Modified Task:

- Altered the true reward to be 1 in an interval $[-0.72, -0.32]$ centered around the bottom of the hill and 0 everywhere else.
- Discount factor $\gamma=0.99$.
- The optimal policy is to move quickly to the bottom of the hill and park there, if possible.
- The algorithm was run on this modified problem.
- Successfully recovers the main structure of the reward, with an artifact on the right side, potentially from the effect of occasionally "shooting off" the right end.
- Overall, considered a fairly good solution for the problem.



Ng, A. Y., & Russell, S.
(2000). Algorithms for
inverse reinforcement
learning. Proc. ICML

IRL from Sampled Trajectories

III. IRL from Sampled Trajectories

- This section addresses the IRL problem in a more **realistic scenario** where the policy π is **known only through a set of actual trajectories in the state space**, rather than having access to the explicit model of the Markov Decision Process (MDP). The goal is to find the reward function R that maximizes the expected return under the given trajectories.
 - The initial state distribution D is fixed.
 - The reward function R is assumed to be expressed using a linear function-approximator class, similar to the approach taken in the previous section for infinite state spaces.
 - For each policy π that we will consider (including the optimal one), we will need a way of estimating $V^\pi(s_o)$ for any setting of the α 's.
-

III. IRL from Sampled Trajectories

For each policy π that we will consider (including the optimal one), we will need a way of estimating $V^\pi(s_0)$ for any setting of the α_i s. To do this, we first execute m Monte Carlo trajectories under π . Then, for each $i = 1, \dots, d$, define $\hat{V}_i^\pi(s_0)$ to be what the average empirical return would have been on these m trajectories if the reward had been $R = \phi_i$. For example, if we take only $m = 1$ trajectories, and if that trajectory visited the sequence of states (s_0, s_1, \dots) , then we have:

$$\hat{V}_i^\pi(s_0) = \phi_i(s_0) + \gamma\phi_i(s_1) + \gamma^2\phi_i(s_2) + \dots$$

In general, $\hat{V}_i^\pi(s_0)$ would be the average over the empirical returns of m such trajectories.² Then, for any setting of the α_i s, a natural estimate of $V^\pi(s_0)$ is:

$$\hat{V}^\pi(s_0) = \alpha_1 \hat{V}_1^\pi(s_0) + \dots + \alpha_d \hat{V}_d^\pi(s_0) \quad (11)$$

III. IRL from Sampled Trajectories

Algorithm:

- Obtain value estimates for the assumed optimal policy π^* and a randomly chosen policy π_1 .
- From the set of policies $\{\pi_1, \dots, \pi_k\}$, the goal is to find a setting of the coefficients α_i in the linear function-approximator class, such that the resulting reward function satisfies

$$V^{\pi^*}(s_0) \geq V^{\pi_i}(s_0), \quad i = 1, \dots, k \quad (12)$$

- Modify the objective function to maximize the penalized difference between the value estimates under the assumed optimal policy (π^*) and each policy in the current set.

$$\begin{aligned} & \text{maximize} \quad \sum_{i=1}^k p \left(\hat{V}^{\pi^*}(s_0) - \hat{V}^{\pi_i}(s_0) \right) \\ & \text{s.t.} \quad |\alpha_i| \leq 1, \quad i = 1, \dots, d \end{aligned} \quad \text{where} \quad p(r) = \begin{cases} r & \text{if } r \geq 0 \\ 2r & \text{otherwise} \end{cases}$$

III. IRL from Sampled Trajectories

Algorithm:

- Solve this linear programming problem to obtain a new setting of coefficients α_i , and consequently, a new reward function $R = \alpha_1 \phi_1 + \alpha_2 \phi_2 + \dots + \alpha_d \phi_d$
 - Find a new policy π_{k+1} that maximizes $V^*(s_0)$ under the newly obtained reward function R .
 - Add π_{k+1} to the current set of policies.
 - Repeat the inductive step for a large number of iterations until a satisfactory reward function is found.
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Continuous Grid World

Experiment 3: Continuous Grid World

- In this experiment, the continuous version of the 5x5 grid world was considered, with the state space being $[0, 1] \times [0, 1]$.
 - The agent could take actions corresponding to the four compass directions, but with the added complexity of noise and truncation to keep the state within the unit square.
 - The true reward was set to 1 in a specific square ($[0.8, 1] \times [0.8, 1]$) and 0 everywhere else, with a discount factor (γ) of 0.9.
 - The reward function was modeled using a function approximator class consisting of all linear combinations of a 15×15 array of two-dimensional Gaussian basis functions. This choice allowed for a flexible representation of the reward function.
 - The initial state distribution D was uniform over the state space, indicating that the agent could start from any point in the $[0, 1] \times [0, 1]$ region.
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Experiment 3: Continuous Grid World

- The algorithm was a sample-based approach, and it was run using 5000 trajectories, each consisting of 30 steps, to evaluate each policy. The MDP was solved when needed, based on a 50×50 discretization of the state space.
 - The performance of the algorithm was evaluated by comparing the optimal policy derived from the fitted reward function with the true optimal policy. The comparison included calculating the fraction of the state space where their action choices disagreed.
 - The algorithm typically produced reasonable solutions after just one iteration. By about 15 iterations, the algorithm had usually settled on fairly good solutions. Discrepancies between the fitted reward's optimal policy and the true optimal policy were found to be between 3% and 10%, which is expected due to the presence of many distinct near-optimal policies.
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Experiment 3: Continuous Grid World

- The quality of the fitted reward's optimal policy was compared with the quality of the true optimal policy, with quality being measured using the true reward function.
- After about 15 iterations, evaluations were unable to detect a statistically significant difference between the value of the true optimal policy and the value of the fitted reward's optimal policy.

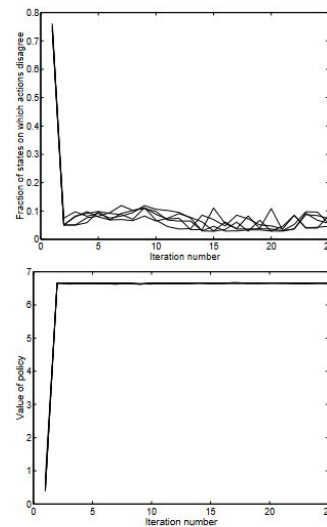
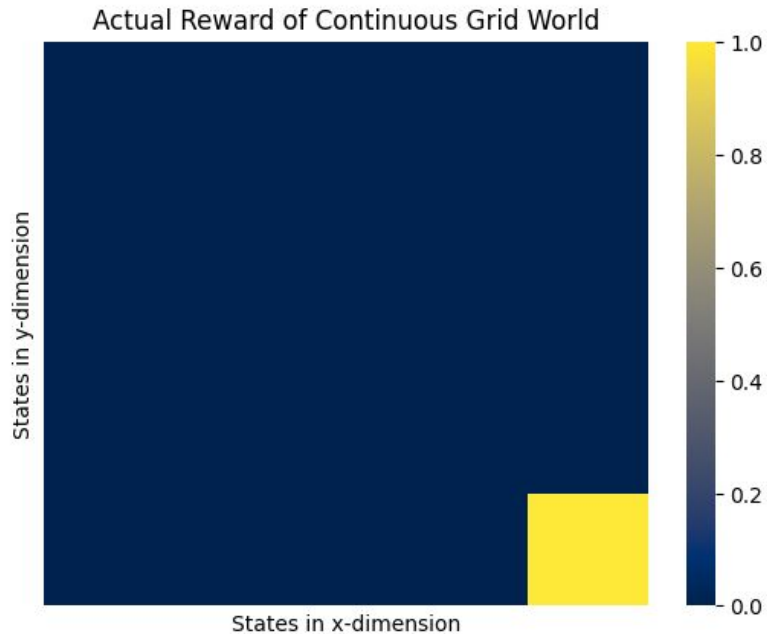
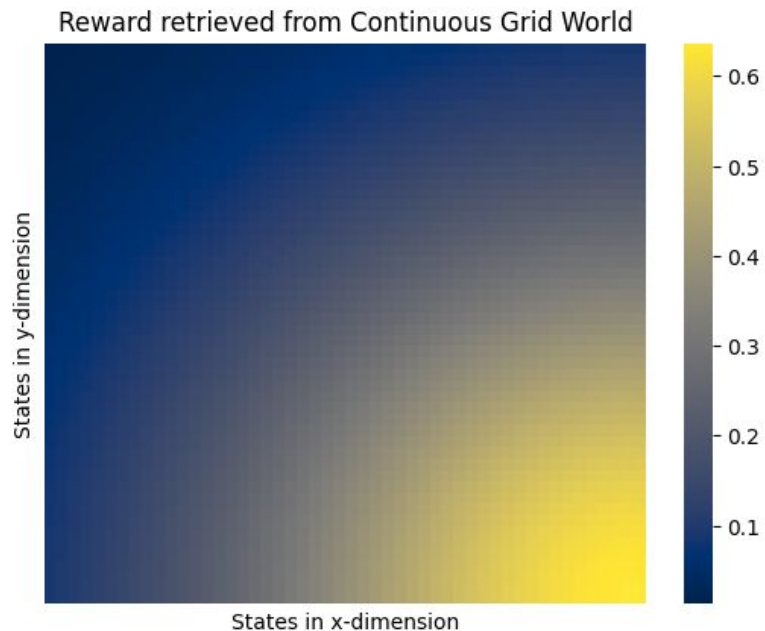


Figure 5. Results on the continuous grid world, for 5 runs. *Top*: Fraction of states on which the fitted reward's optimal policy disagrees with the true optimal policy, plotted against iteration number. *Bottom*: The value of the fitted reward's optimal policy. (Estimates are from 50000 Monte Carlo trials of length 50 each; negligible errorbars).

Experiment 3: Continuous Grid World



Experiment 3: Continuous Grid World



Conclusion

The results indicate that the inverse reinforcement learning (IRL) problem is solvable, particularly for moderate-sized discrete and continuous domains. This implies that IRL algorithms can effectively recover reward functions from observed behavior.

Thank You

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