#### plain text (0.92)

## We'll consider the terms with Q and b in tur 0

$$\mathbb{E}_{s_{0:\infty},a_{0:\infty}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) Q_t(s_{0:\infty},a_{0:\infty}) \right]$$

$$= \mathbb{E}_{s_{0:t},a_{0:t}} \left[ \mathbb{E}_{s_{t+1:\infty},a_{t+1:\infty}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) Q_t(s_{0:\infty},a_{0:\infty}) \right] \right]$$

$$= \mathbb{E}_{s_{0:t},a_{0:t}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) \mathbb{E}_{s_{t+1:\infty},a_{t+1:\infty}} \left[ Q_t(s_{0:\infty},a_{0:\infty}) \right] \right]$$

$$= \mathbb{E}_{s_{0:t},a_{0:t-1}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) A^{\pi}(s_t,a_t) \right]$$

# plain\_text (0.91)

Ne: 2

isolate\_formula (0.96)

$$\mathbb{E}_{s_{0:\infty},a_{0:\infty}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) b_t(s_{0:t}, a_{0:t-1}) \right] \\
= \mathbb{E}_{s_{0:t},a_{0:t-1}} \left[ \mathbb{E}_{s_{t+1:\infty},a_{t:\infty}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) b_t(s_{0:t}, a_{0:t-1}) \right] \right] \\
= \mathbb{E}_{s_{0:t},a_{0:t-1}} \left[ \mathbb{E}_{s_{t+1:\infty},a_{t:\infty}} \left[ \nabla_{\theta} \log \pi_{\theta}(a_t \mid s_t) \right] b_t(s_{0:t}, a_{0:t-1}) \right] \\
= \mathbb{E}_{s_{0:t},a_{0:t-1}} \left[ 0 \cdot b_t(s_{0:t}, a_{0:t-1}) \right] \\
= 0.$$

### title (0.87)

### REFERENCE 4

Barto, Andrew G, Sutton, Richard S, and Anderson, Charles W. Neuronlike adaptive elements that can sol difficult learning control problems. *Systems, Man and Cybernetics, IEEE Transactions on*, (5):834–846, 1983

Baxter, Jonathan and Bartlett, Peter L. Reinforcement learning in POMDPs via direct gradient ascent. In ICML, pp. 41–48, 2000.

Bertsekas, Dimitri P. Dynamic programming and optimal control, volume 2. Athena Scientific, 2012.

Bhatnagar, Shalabh, Precup, Doina, Silver, David, Sutton, Richard S, Maei, Hamid R, and Szepesvári, Csaba. Convergent temporal-difference learning with arbitrary smooth function approximation. In *Advances in Neural Information Processing Systems*, pp. 1204–1212, 2009.

Greensmith, Evan, Bartlett, Peter L, and Baxter, Jonathan. Variance reduction techniques for gradient estimates in reinforcement learning. *The Journal of Machine Learning Research*, 5:1471–1530, 2004.

Hafner, Roland and Riedmiller, Martin. Reinforcement learning in feedback control. *Machine learning*, 84 (1-2):137–169, 2011.

Heess, Nicolas, Wayne, Greg, Silver, David, Lillicrap, Timothy, Tassa, Yuval, and Erez, Tom. Learning continuous control policies by stochastic value gradients. arXiv preprint arXiv:1510.09142, 2015.

Hull, Clark. Principles of behavior. 1943.

Kakade, Sham. A natural policy gradient. In NIPS, volume 14, pp. 1531–1538, 2001a.

Kakade, Sham. Optimizing average reward using discounted rewards. In Computational Learning Theory, pp. 605–615. Springer, 2001b.

Kimura, Hajime and Kobayashi, Shigenobu. An analysis of actor/critic algorithms using eligibility traces: Reinforcement learning with imperfect value function. In *ICML*, pp. 278–286, 1998.

Konda, Vijay R and Tsitsiklis, John N. On actor-critic algorithms. SIAM journal on Control and Optimization, 42(4):1143–1166, 2003.

Lillicrap, Timothy P, Hunt, Jonathan J, Pritzel, Alexander, Heess, Nicolas, Erez, Tom, Tassa, Yuval, Silver, David, and Wierstra, Daan. Continuous control with deep reinforcement learning. arXiv preprint arXiv:1509.02971, 2015.

Marbach, Peter and Tsitsiklis, John N. Approximate gradient methods in policy-space optimization of markov reward processes. *Discrete Event Dynamic Systems*, 13(1-2):111–148, 2003.

Minsky, Marvin. Steps toward artificial intelligence. Proceedings of the IRE, 49(1):8–30, 1961.

Ng, Andrew Y, Harada, Daishi, and Russell, Stuart. Policy invariance under reward transformations: Theory and application to reward shaping. In *ICML*, volume 99, pp. 278–287, 1999.

Peters, Jan and Schaal, Stefan. Natural actor-critic. Neurocomputing, 71(7):1180–1190, 2008.