

# 2 Environment Anatomy: What the Robot Sees, Does, and Learns From

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## 2 Environment Anatomy: What the Robot Sees, Does, and Learns From

### This chapter covers:

- Inspecting the dictionary observation structure that every Fetch environment returns -- what each number means physically and why observations are dictionaries, not flat vectors
- Understanding what the 4D action vector controls: Cartesian deltas for the end-effector and a gripper open/close command
- Verifying reward computation for both dense (distance-based) and sparse (binary success/failure) variants, and proving the critical invariant that makes Hindsight Experience Replay possible
- Simulating goal relabeling by hand -- calling compute\_reward with goals the environment never intended -- to see why the Fetch interface enables HER
- Establishing a random-policy baseline (success rate, mean return, goal distance) that every trained agent in later chapters must beat

In Chapter 1, you verified that the computational stack works: Docker launches, MuJoCo simulates, the rendering pipeline produces frames, and a training loop runs to completion. You have a proof of life -- evidence that the environment is alive and capable of producing results.

But alive is not the same as understood. You know the environment *works*, but not what it *says*. What do the 10 numbers in the observation vector mean? What happens when the robot takes action [1, 0, 0, 0]? Why does the reward function return -0.073 instead of -1? How does the environment know the robot "succeeded"? Answering these questions gives you the foundation to debug training failures and choose appropriate algorithms.

This chapter provides a complete anatomy of Fetch environment observations, actions, rewards, and goals. You will inspect every component by hand, verify reward computation against the distance formula, simulate HER-style goal relabeling, and establish the random-policy baseline that every trained agent must beat. With the environment understood, Chapter 3 trains a real policy -- PPO on dense Reach -- where the observation shapes you document here determine the network architecture, and the random baseline you establish here is the floor that PPO must exceed.

## 2.1 WHY: Why environment anatomy matters

Imagine you train a policy for 10 hours. The training loop completes without errors. You evaluate the checkpoint and find a success rate of 0%. You check the reward curve -- flat. You check the loss -- it looks normal. Nothing crashed. What went wrong?

Understanding what the agent sees and what rewards mean is what makes this question answerable. The problem could be anywhere: the observations might have unexpected scales, the rewards might have the wrong sign, the success threshold might be different from what you assumed, or the goal structure might not match what the algorithm expects. Knowing the environment anatomy turns a 10-hour mystery into a 10-minute diagnostic.

In our experience, environment misunderstandings are the most common source of wasted compute in robotics RL -- more than bad hyperparameters or wrong algorithms. The root cause is usually wrong assumptions about what the environment is actually doing.

### Three questions that anatomy answers

Here are three questions that come up in every training failure. Each one becomes straightforward once you have inspected the environment:

**1. "Is the observation what the network expects?"** When you create a policy with SB3's `MultiInputPolicy`, it reads the observation space to determine its input structure. If the observation is a dictionary with three keys, the network builds three separate encoders and concatenates them. If the observation were somehow a flat vector (due to a wrapper or version mismatch), the network architecture would be completely different -- and wrong for the task. You need to know exactly what the observation contains to understand what the network receives.

**2. "Is the reward on a reasonable scale?"** Dense Fetch rewards are negative distances -- typical values in the range -0.01 to -0.3 for `FetchReach`. If you tuned your learning rate assuming rewards on the order of -1 to 0 (as with sparse rewards), your value function targets would be off by an order of magnitude. Reward scale affects everything: the value function's target range, the entropy coefficient in SAC, and the advantage normalization in PPO.

**3. "Can this environment support HER?"** Hindsight Experience Replay -- which we introduce in Chapter 5 -- requires two specific properties from the environment: an explicit `achieved_goal` in the observation, and a `compute_reward` function that accepts

arbitrary goals. If either is missing, HER cannot work. Checking these properties upfront saves you from a frustrating debugging session where the problem is structural, not algorithmic -- a distinction that is much easier to spot before training than after.

## What misunderstandings cost

To be concrete about the cost, here is a table of misunderstandings we have seen (some in our own work, some reported by others) and what they led to:

Misunderstanding	What happens
Assumed observations are flat vectors	Network architecture wrong
Did not know <code>achieved_goal</code> tracks object (not gripper) in <code>FetchPush</code>	Reward calculations wrong
Assumed sparse reward is <code>-1/+1</code> (it is <code>-1/0</code> )	Value function targets off; c
Did not verify <code>compute_reward</code> matches <code>env.step()</code>	HER learns from corrupted
Did not check success threshold	Evaluated with wrong succ

The common thread: every one of these is preventable by inspecting the environment before training. This chapter does that inspection systematically.

## The anatomy as a debugging foundation

When you understand what the environment returns, debugging becomes tractable. A flat reward curve is no longer a mystery -- you can check: does the policy's output fall within the action space bounds? Is the achieved goal moving in response to actions? Is the reward decreasing (getting closer to zero) even if success rate has not budged? Is `compute_reward` returning the same values as `env.step()`?

Each of these diagnostic checks has a specific prerequisite in this chapter's anatomy. Checking action bounds requires knowing the action space shape and range (section 2.4), while checking goal movement requires knowing what `achieved_goal` tracks - gripper position for `Reach`, object position for `Push` (section 2.3). Checking reward trends requires knowing the reward formula and its range, since dense rewards are negative distances and sparse rewards are 0 or -1 (section 2.5). And checking the `compute_reward` invariant requires knowing the API signature and how it relates to `env.step()` (also section 2.5).

All of these will come up in practice. In Chapter 3, when PPO training stalls, the first thing to check is whether the reward is moving. In Chapter 5, when HER does not improve performance, the first thing to check is whether `compute_reward` handles relabeled goals correctly. The anatomy you build here is the diagnostic toolkit for every later chapter.

The rest of this chapter gives you that knowledge, piece by piece. We start with what the agent sees (observations and goals), move to what it can do (actions), then to how performance is measured (rewards), and finally to the key insight that ties it all together (goal relabeling).

## The goal-conditioned MDP: seven pieces

The Fetch environments implement a specific mathematical structure called a *goal-conditioned Markov Decision Process* (GCMDP). Here is what we mean by that -- not as a formal theorem, but as a concrete description of the interface you will work with.

A goal-conditioned MDP has seven pieces:

- **States** ( $\mathcal{S}$ ): the full physical state of the robot and any objects on the table
- **Actions** ( $\mathcal{A}$ ): what the robot can do (4D Cartesian deltas plus gripper)
- **Goals** ( $\mathcal{G}$ ): the target positions the robot must achieve (3D Cartesian coordinates)
- **Transitions** ( $P$ ): the physics -- how the state changes when the robot acts
- **Rewards** ( $R$ ): the feedback signal, which depends on the goal
- **Goal-achievement mapping** ( $\phi$ ): a function that extracts "what goal did we achieve?" from the current state
- **Discount factor** ( $\gamma$ ): how much we value future rewards versus immediate ones

The critical insight is that the reward depends on the goal. The same state might yield reward -0.1 for one goal (you are close) and -0.5 for another (you are far away). And the goal-achievement mapping  $\phi$  tells us what goal we *actually* achieved, regardless of what goal we were aiming for. These two properties -- goal-dependent rewards and an explicit achieved goal -- are what make Hindsight Experience Replay possible. We will see exactly why in section 2.6.

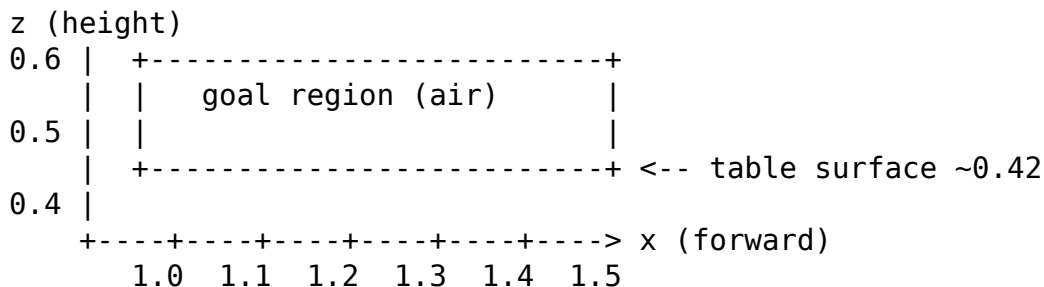
## 2.2 The Fetch task family

Chapter 1 introduced the four Fetch tasks: Reach, Push, PickAndPlace, and Slide. Here we add the physical details that matter for environment anatomy.

**The simulated robot.** The Fetch arm is a 7-degree-of-freedom manipulator modeled in MuJoCo, a rigid-body physics simulator. MuJoCo runs the physics at 500 Hz internally; the environment exposes control at 25 Hz (every 20 simulation steps). When you call `env.step(action)`, MuJoCo simulates 20 timesteps of physics, then returns the resulting state.

**The workspace.** The arm sits on a fixed base next to a table. The workspace -- the region where goals are sampled and the end-effector can reach -- spans roughly:

Fetch Workspace (approximate bounds in meters):



y (sideways) spans roughly 0.5 to 1.0 (goal region)

When you render this scene, the coordinates come to life. The tan tabletop sits at  $z=0.42$  -- about kitchen-counter height in the simulation. The silver arm links rise from a fixed base at the table's edge, and the gripper hovers at roughly  $z=0.53$ , just above where you would rest your elbow. A small red sphere marks the target goal, floating somewhere in the air above the table. The workspace numbers above map directly onto this visual:  $x$  runs forward away from the base,  $y$  spans the table side to side, and  $z$  measures height above the floor.

These numbers matter because they give you a sense of scale. The entire workspace is about 60 cm x 70 cm x 20 cm. The success threshold is 5 cm (0.05 m), which means the end-effector must be within about 8% of the workspace width to "succeed." Random flailing is unlikely to land within 5 cm of an arbitrary target -- which is why random baselines have near-zero success rates.

**Dense vs. sparse rewards.** Each task comes in two reward variants, and the environment ID encodes which: `FetchReachDense-v4` uses dense rewards (negative distance to goal), while `FetchReach-v4` uses sparse rewards (0 if goal reached, -1 otherwise). The observation structure and action space are identical between variants -- only the reward computation differs.

For this chapter, we work primarily with `FetchReachDense-v4` (dense Reach). It is the simplest variant: no objects, continuous feedback, and a workspace that the arm can easily cover. The anatomy principles transfer directly to `Push`, `PickAndPlace`, and `Slide` -- the interface is the same, and we verify that uniformity in section 2.7. Figures 2.1 through 2.3 show the three Fetch environments we use in this book.

## Fetch Reach

Task: Move gripper to target

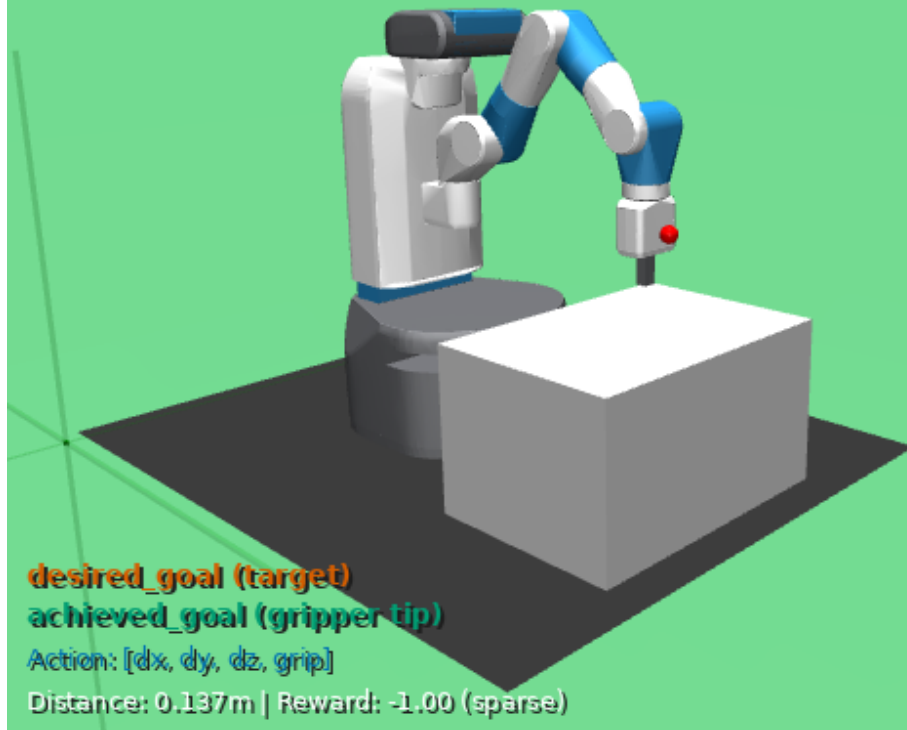


Figure 2.1: FetchReach-v4 after `env.reset()`. The silver arm extends over a tan tabletop, its parallel-jaw gripper (`achieved_goal`) hovering in the air. A small red sphere marks the target (`desired_goal`). No objects are involved -- this is pure arm positioning. (Generated by `bash docker/dev.sh python scripts/capture_proposal_figures.py env-setup --envs FetchReach-v4.`)

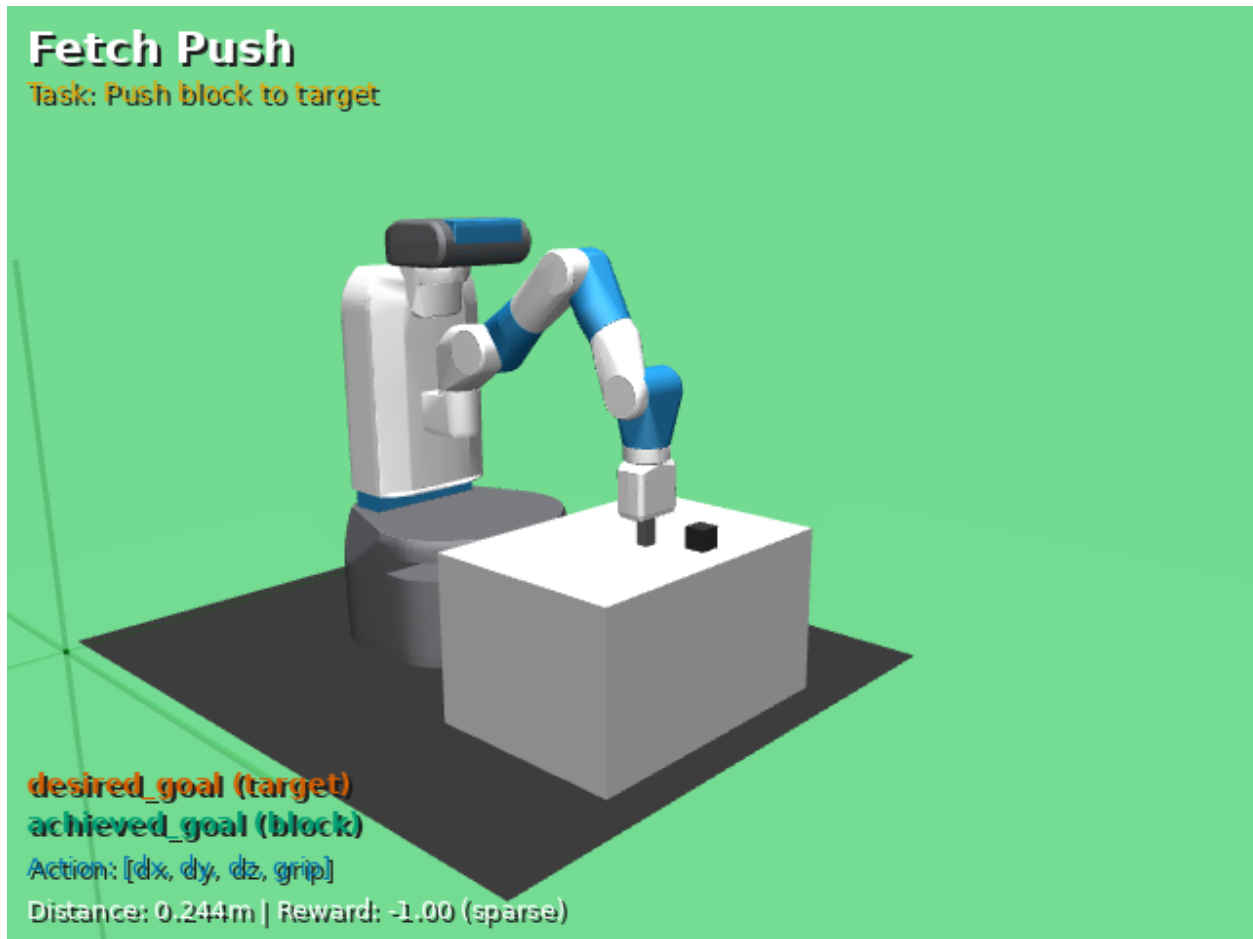


Figure 2.2: FetchPush-v4 after `env.reset()`. A dark cube rests on the tan tabletop; a red marker on the surface shows where it needs to go. The robot must slide the block across the table to that target position. Here, `achieved_goal` is the block's position (not the gripper's), and `desired_goal` is where the block should end up. (Generated by `bash docker/dev.sh python scripts/capture_proposal_figures.py env-setup --envs FetchPush-v4.`)



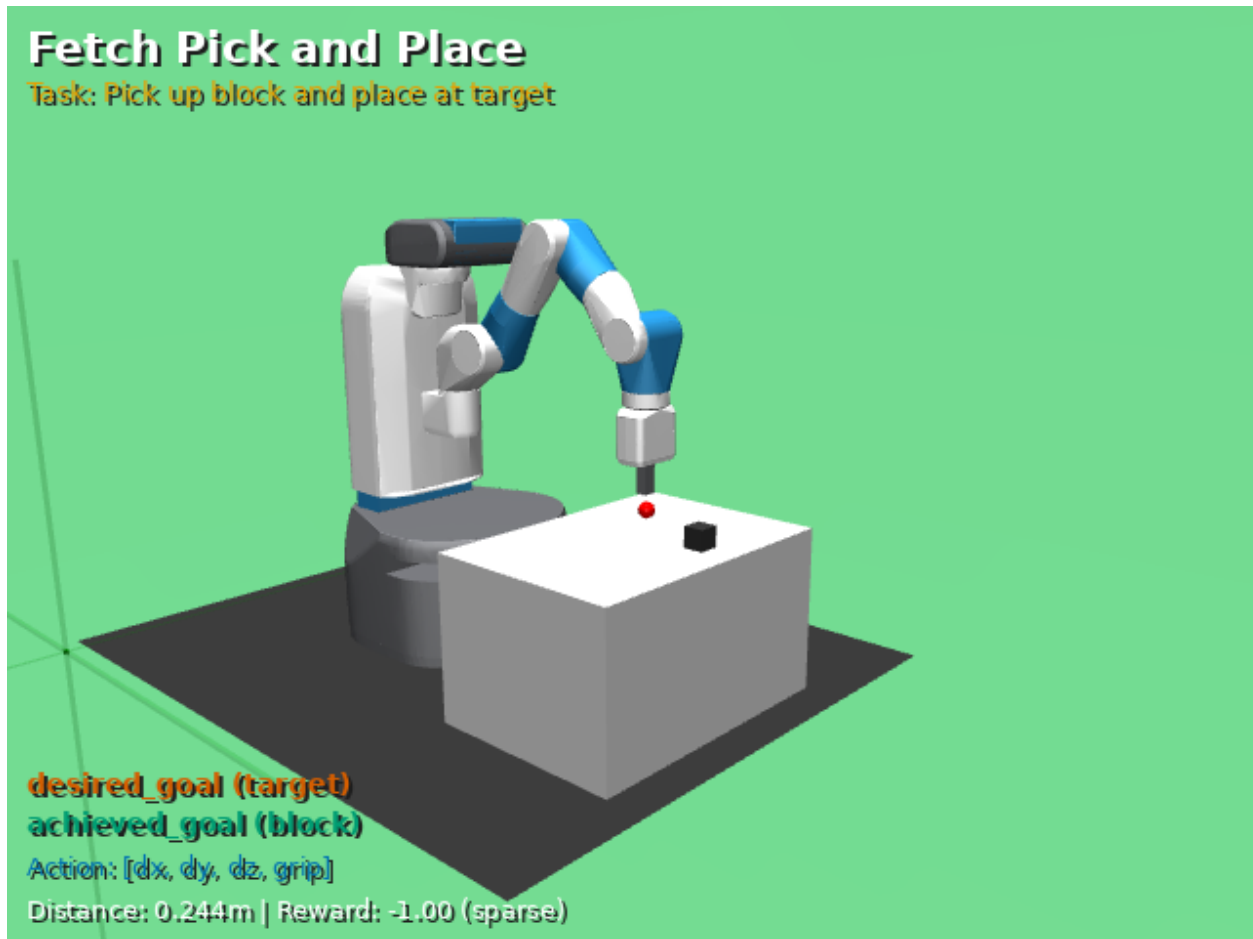


Figure 2.3: FetchPickAndPlace-v4 after `env.reset()`. The red target sphere floats in the air above the table -- visibly higher than in Push, signaling that the robot must lift the block off the surface. The robot must pick up the block and place it at that suspended target position, coordinating grasping, lifting, and releasing. (Generated by `bash docker/dev.sh python scripts/capture_proposal_figures.py env-setup --envs FetchPickAndPlace-v4`.)

**Episode structure.** Every episode lasts exactly 50 steps (the environment truncates at this limit). At each step, the agent observes the state, chooses an action, and receives a reward. The episode ends when the step limit is reached -- there is no early termination on success. This means that even a successful policy continues to act for the full 50 steps, which affects how you interpret returns: a policy that reaches the goal on step 10 still receives rewards for the remaining 40 steps. For dense rewards, those remaining steps contribute small negative values (the agent is near the goal). For sparse rewards, they contribute 0s (the agent has already succeeded).

## 2.3 Build It: The observation dictionary

The first thing to understand about any RL environment is what the agent perceives. In Fetch environments, the agent does not see a flat vector but rather a dictionary with three keys, each carrying a different kind of information. This structure is not just a

data format -- it is the interface through which goal-conditioned learning operates.

## What the dictionary contains

The observation dictionary has three entries:

- `obs["observation"]` -- the robot's proprioceptive state. For FetchReach, this is a 10-dimensional vector containing the gripper's position, velocity, and finger state.
- `obs["achieved_goal"]` -- where the relevant thing (end-effector for Reach, object for Push) currently is. Always 3D Cartesian coordinates.
- `obs["desired_goal"]` -- where we want that thing to be. Also 3D Cartesian coordinates.

The separation of achieved and desired goals from the main observation is the key design decision. It makes the goal-conditioning explicit: the environment tells the agent "here is your state, here is where you are, here is where you need to be."

Why not a flat vector? Many RL environments (CartPole, Atari, MuJoCo locomotion) return a single array as the observation. Fetch environments *could* concatenate everything into a flat vector of length 16 (for Reach) or 31 (for Push). But the dictionary structure serves two purposes. First, it makes the goal-conditioned interface explicit -- the achieved and desired goals are labeled, not buried at arbitrary indices in a flat vector. Second, it enables SB3's `MultiInputPolicy` to process each component through a separate encoder before concatenation, which gives the network a natural way to compare "where I am" against "where I should be."

## Inspecting the observation

**Note:** All code listings in this chapter assume `import gymnasium as gym`, `import gymnasium_robotics`, and `import numpy as np`. The full runnable versions live in `scripts/labs/env_anatomy.py`.

Let's look at the code that inspects this structure:

```
# Observation dictionary inspector
# (adapted from scripts/labs/env_anatomy.py:obs_inspector)

def obs_inspector(env_id="FetchReachDense-v4", seed=0):
    """Inspect obs dict: keys, shapes, dtypes, workspace bounds."""
    env = gym.make(env_id)
    obs, info = env.reset(seed=seed)
    summary = {}
    for key in ["observation", "achieved_goal", "desired_goal"]:
        arr = np.asarray(obs[key])
        summary[key] = {
            "shape": arr.shape, "dtype": str(arr.dtype),
            "min": float(arr.min()), "max": float(arr.max()),
            "finite": bool(np.all(np.isfinite(arr))),
        }
    # Check desired_goal is within workspace
```

```

dg = np.asarray(obs["desired_goal"])
summary["desired_goal_in_workspace"] = bool(
    1.1 <= dg[0] <= 1.5 and 0.5 <= dg[1] <= 1.0
    and 0.35 <= dg[2] <= 0.75
)
env.close()
return summary

```

**Checkpoint.** Run `bash docker/dev.sh python scripts/labs/env_anatomy.py --verify` and check the first output section. You should see:

- `obs=(10,)`, `ag=(3,)`, `dg=(3,)`
- All values finite
- `desired_goal in workspace: True`

If the observation shape is not `(10,)`, check that you are using `FetchReachDense-v4` (not a `Push` or `PickAndPlace` variant, which have 25D observations).

## The 10D observation breakdown

What do those 10 numbers actually represent? Here is the breakdown for `FetchReach`:

Index	Semantic	Units	Typical range
0-2	Gripper position (x, y, z)	meters	[1.1, 1.5], [0.5, 1.0], [0.35, 0.75]
3-4	Gripper finger positions (right, left)	meters	[0.0, 0.05]
5-7	Gripper linear velocity (dx, dy, dz)	m/s	[-0.1, 0.1]
8-9	Gripper finger velocities (right, left)	m/s	[-0.01, 0.01]

For `FetchReach`, the first three elements of `obs["observation"]` -- the gripper position -- are the same as `obs["achieved_goal"]`. This is because the goal-achievement mapping  $\phi$  for reaching is: "where is the end-effector?" We can verify this:

## The goal space: where goals live

The goal-achievement mapping  $\phi$  extracts the "achieved goal" from the current state -- for `Reach`,  $\phi(s)$  is the gripper position, while for `Push`,  $\phi(s)$  is the object position. This mapping is what determines `achieved_goal` in the observation dictionary.

```

# Goal space verification
# (adapted from scripts/labs/env_anatomy.py:goal_space)

def goal_space(env_id="FetchReachDense-v4", n_resets=100, seed=0):
    """Sample goals via reset; check bounds; verify  $\phi(s)=obs[:3]$ ."""
    env = gym.make(env_id)
    desired_goals, phi_matches = [], []
    for i in range(n_resets):
        obs, _ = env.reset(seed=seed + i)

```

```

desired_goals.append(np.asarray(obs["desired_goal"]))
ag = np.asarray(obs["achieved_goal"])
obs_vec = np.asarray(obs["observation"])
# phi(s) = grip_pos = obs["observation"][:3] for FetchReach
phi_matches.append(bool(np.allclose(ag, obs_vec[:3])))
dg_arr = np.stack(desired_goals)
env.close()
return {
    "n_resets": n_resets,
    "goal_dim": int(dg_arr.shape[1]),
    "desired_goal_bounds": {
        "min": dg_arr.min(axis=0).tolist(),
        "max": dg_arr.max(axis=0).tolist(),
    },
    "all_phi_match": all(phi_matches),
}

```

**Checkpoint.** The verification output should show:

- goal\_dim=3
- phi matches obs[:3]: True (all 100 resets)
- desired\_goal range: within the workspace (roughly x in [1.1, 1.5], y in [0.5, 1.0], z in [0.35, 0.75])

If `phi matches obs[:3]` is False for any reset, there is a version mismatch in gymnasium-robotics. If the goal range is very narrow (all coordinates nearly identical), the environment is not randomizing goals correctly -- check your seed handling.

## What the policy network will see

When we create an SB3 model with `MultiInputPolicy` in Chapter 3, the network reads this dictionary observation space and builds the architecture shown in Figure 2.4:

Network input	Source key	Dimensions
State encoder	observation	10
Achieved goal encoder	achieved_goal	3
Desired goal encoder	desired_goal	3
<b>Total input</b>	(concatenated)	<b>16</b>

The encoders process each key through separate MLP layers, then concatenate the results before passing through shared layers. The total input dimension -- 16 for FetchReach, 31 for FetchPush -- determines the network's capacity requirements. This is why we document shapes carefully: they directly affect architecture.

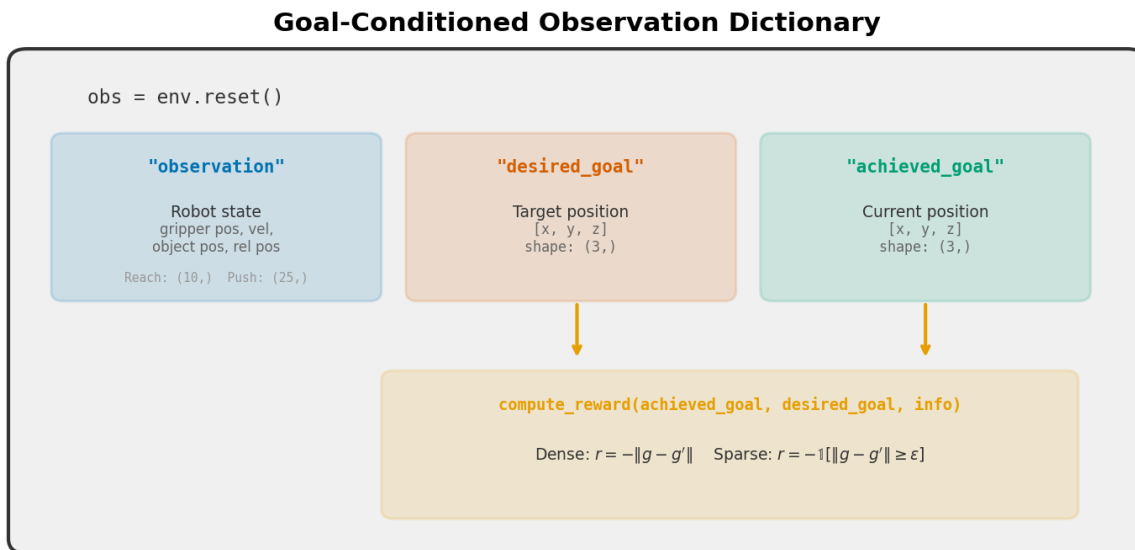


Figure 2.4: The observation dictionary structure and how it maps to the policy network. Each key in the dictionary (observation, achieved\_goal, desired\_goal) feeds a separate encoder in SB3's MultiInputPolicy. The outputs are concatenated into a single feature vector (16D for FetchReach, 31D for FetchPush) before passing through shared layers. (Generated by `bash docker/dev.sh python scripts/capture_proposal_figures.py reward-diagram.`)

## 2.4 Build It: Action semantics

The agent does not control joint torques. Instead, it outputs a 4-dimensional vector of Cartesian commands that an internal controller translates into joint movements. This is an important design choice: the learning algorithm does not need to solve inverse kinematics, which makes the learning problem more tractable.

### What each action dimension controls

Index	Semantic	Range	Physical effect
0	dx	[-1, 1]	End-effector moves in the x direction (forward/backward)
1	dy	[-1, 1]	End-effector moves in the y direction (left/right)
2	dz	[-1, 1]	End-effector moves in the z direction (up/down)
3	grripper	[-1, 1]	< 0 opens, > 0 closes the parallel-jaw gripper

Actions are clipped to [-1, 1] and then scaled by the environment's internal controller before being applied as forces. The scaling means that action [1, 0, 0, 0] does not move the end-effector by exactly 1 meter -- it applies a maximal positive displacement command along x, and the actual movement depends on the physics simulation (friction, inertia, joint limits).

## Verifying action-to-movement mapping

We can verify that each action axis produces movement in the expected direction:

```
# Action space explorer
# (adapted from scripts/labs/env_anatomy.py:action_explorer)

def action_explorer(env_id="FetchReachDense-v4", seed=0):
    """Step with axis-aligned actions, measure displacement."""
    env = gym.make(env_id)
    results = {
        "action_shape": env.action_space.shape,
        "action_low": env.action_space.low.tolist(),
        "action_high": env.action_space.high.tolist(),
        "displacements": {},
    }
    axis_names = ["x", "y", "z"]
    for axis_idx in range(3):
        obs, _ = env.reset(seed=seed)
        grip_before = np.asarray(obs["achieved_goal"]).copy()
        action = np.zeros(4, dtype=np.float32)
        action[axis_idx] = 1.0
        obs, _, _, _ = env.step(action)
        grip_after = np.asarray(obs["achieved_goal"])
        disp = grip_after - grip_before
        results["displacements"][axis_names[axis_idx]] = {
            "action": action.tolist(),
            "displacement": disp.tolist(),
            "moved_positive": bool(disp[axis_idx] > 0),
        }
    env.close()
    return results
```

**Checkpoint.** The verification output should show:

- action\_shape=(4,), bounds [-1, 1]
- Action [1,0,0,0] produces positive x displacement
- Action [0,1,0,0] produces positive y displacement
- Action [0,0,1,0] produces positive z displacement

The displacement magnitudes are small (typically 0.005-0.02 meters per step) because the action is applied for one 25 Hz control step. At 50 steps per episode, the end-effector can traverse roughly 0.25-1.0 meters total -- enough to cover the workspace.

For FetchReach, the gripper dimension (index 3) has no effect on the task -- there is no object to grasp. For Push and PickAndPlace, it becomes essential: the agent must learn to close the gripper around an object and open it at the target location.

**Warning:** A subtle point about action semantics: the policy outputs continuous values in [-1, 1], but the mapping from these values to physical displace-

ment is not linear and depends on MuJoCo's internal controller. An action of  $[0.5, 0, 0, 0]$  does not produce exactly half the displacement of  $[1.0, 0, 0, 0]$ . In practice, this does not matter for training -- the policy learns the mapping implicitly -- but it means you should not try to hand-code a controller using these action values as if they were calibrated velocity commands.

## 2.5 Build It: Reward computation -- dense and sparse

Now that we know what the agent sees and what it can do, we need to understand how the environment evaluates performance. Fetch environments provide two reward variants, and understanding both is essential for the rest of the book.

### Dense reward: negative distance

The dense reward for any Fetch environment is:

$$R_{\text{dense}} = -\|g_a - g_d\|_2$$

where  $g_a$  is the achieved goal (a 3D position),  $g_d$  is the desired goal (also 3D), and  $\|\cdot\|_2$  is the Euclidean norm. The reward is always negative or zero, with zero meaning perfect goal achievement. A reward of -0.1 means the relevant point (end-effector for Reach, object for Push) is 10 cm from the target.

This reward provides continuous gradient information: every action that moves closer to the goal produces a less negative reward. Standard policy gradient methods like PPO can learn effectively from this signal because there is always a direction to improve.

### Verifying the dense reward formula

We verify that three things match: the manual distance formula, the `compute_reward` API, and the reward returned by `env.step()`.

```
# Dense reward check
# (adapted from scripts/labs/env_anatomy.py:dense_reward_check)

def dense_reward_check(env_id="FetchReachDense-v4", n_steps=100,
                       seed=0, atol=1e-10):
    """Verify  $R = -\|ag - dg\|$  matches step_reward and compute_reward."""
    env = gym.make(env_id)
    obs, info = env.reset(seed=seed)
    mismatches = 0
    for t in range(n_steps):
        action = env.action_space.sample()
        obs, step_reward, terminated, truncated, info = env.step(action)
        ag = np.asarray(obs["achieved_goal"])
        dg = np.asarray(obs["desired_goal"])
        manual = -float(np.linalg.norm(ag - dg))
        cr = float(
```

```

        env.unwrapped.compute_reward(ag, dg, info))
    step_r = float(step_reward)
    if abs(manual - cr) > atol or abs(manual - step_r) > atol:
        mismatches += 1
    if terminated or truncated:
        obs, info = env.reset(seed=seed + t + 1)
env.close()
return {"n_steps": n_steps, "mismatches": mismatches}

```

This three-way comparison is the heart of the verification. We compute the reward ourselves (`manual`), ask the environment to compute it (`cr`), and compare both to what `env.step()` returned (`step_r`). All three must agree.

Why do we check all three? Because each catches a different failure mode. If `manual` differs from `cr`, our understanding of the reward formula is wrong -- maybe the reward is not just negative distance, but includes a scaling factor or an offset. If `cr` differs from `step_r`, there is a bug in the environment or a version mismatch between the wrapper and the base environment. If `manual` matches `cr` but not `step_r`, the wrapper is modifying the reward (perhaps adding a penalty term). Any of these mismatches would corrupt HER's relabeling in Chapter 5.

**Checkpoint.** Over 100 steps: zero mismatches, tolerance  $1e-10$ . The three values should match to floating-point precision. If they do not match, you likely have a version mismatch between `gymnasium` and `gymnasium-robotics`.

## Sparse reward: binary success signal

As Figure 2.5 illustrates, the sparse reward works very differently from the dense variant: instead of a smooth gradient, the agent receives a binary signal determined by a distance threshold  $\epsilon = 0.05$  meters (5 cm):

$$R_{\text{sparse}} = \begin{cases} 0 & \text{if } \|g_a - g_d\|_2 \leq \epsilon \\ -1 & \text{otherwise} \end{cases}$$

Note the values: 0 for success and -1 for failure -- not +1 for success, not -1/+1. The reward is always non-positive, which matters for value function initialization and for understanding what a "good" return looks like.

Let's trace through the numbers. With sparse rewards, an episode of 50 steps where the goal is never reached has a return of  $\sum_{t=0}^{49} (-1) = -50$ . An episode where the goal is reached on step 40 and maintained for the remaining 10 steps has a return of  $40 \times (-1) + 10 \times 0 = -40$ . A perfect policy that reaches the goal immediately would have a return of  $-1 \times (\text{steps to reach goal}) + 0 \times (\text{remaining steps})$ . The best possible return on a 50-step episode is 0 (goal reached on step 0), but in practice even good policies take a few steps to reach the goal, so returns of -2 to -5 indicate strong performance.



For dense rewards, the numbers are different but the reasoning is similar. The return is the sum of negative distances across all 50 steps, so a random policy averages about -25 to -10 per episode, while a well-trained policy that quickly reaches the goal and stays there might achieve -1 to -3.

## Verifying the sparse reward formula

```
# Sparse reward check
# (adapted from scripts/labs/env_anatomy.py:sparse_reward_check)

def sparse_reward_check(env_id="FetchReach-v4", n_steps=100,
                        seed=0, atol=1e-10):
    """Verify  $R = 0$  if  $\|ag - dg\| \leq \epsilon$  else  $-1$ ; check threshold."""
    env = gym.make(env_id)
    eps = float(env.unwrapped.distance_threshold)
    obs, info = env.reset(seed=seed)
    mismatches, non_binary = 0, 0
    for t in range(n_steps):
        action = env.action_space.sample()
        obs, step_reward, terminated, truncated, info = env.step(action)
        ag = np.asarray(obs["achieved_goal"])
        dg = np.asarray(obs["desired_goal"])
        dist = float(np.linalg.norm(ag - dg))
        expected = 0.0 if dist <= eps else -1.0
        step_r = float(step_reward)
        cr_r = float(
            env.unwrapped.compute_reward(ag, dg, info))
        if step_r not in (0.0, -1.0):
            non_binary += 1
        if (abs(step_r - expected) > atol
            or abs(cr_r - expected) > atol):
            mismatches += 1
        if terminated or truncated:
            obs, info = env.reset(seed=seed + t + 1)
    env.close()
    return {"n_steps": n_steps, "threshold": eps,
            "mismatches": mismatches, "non_binary": non_binary}
```

**Checkpoint.** Over 100 steps:

- threshold=0.05
- mismatches=0
- non\_binary=0 (every sparse reward is exactly 0.0 or -1.0)

If the threshold is not 0.05, your gymnasium-robotics version may use a different default. If non-binary count is positive, something unexpected is happening with the reward computation.

## Dense vs Sparse Rewards in Fetch Environments

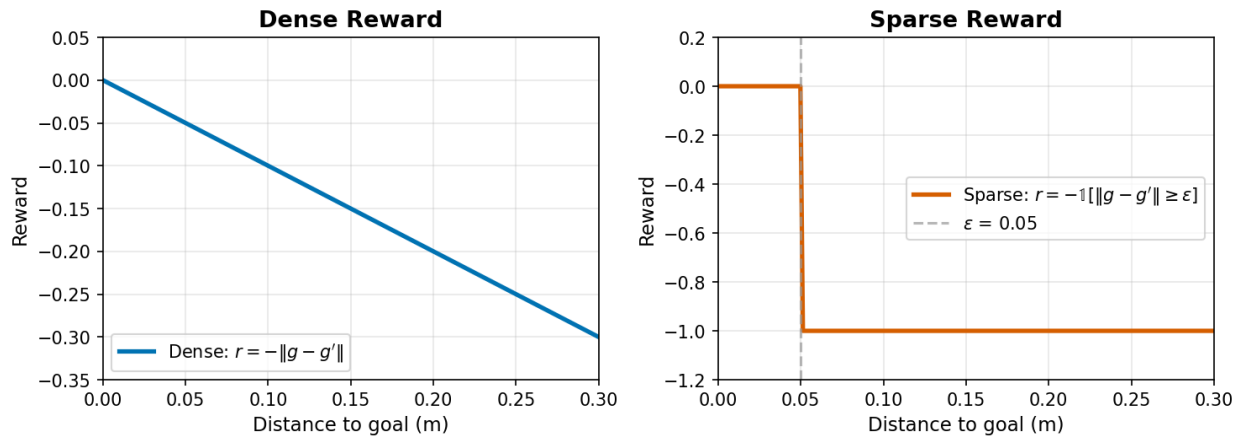


Figure 2.5: Dense vs sparse reward functions. Left: dense reward  $R = -\|g_a - g_d\|$  provides a smooth gradient signal -- every action that reduces distance improves the reward. Right: sparse reward is a step function at the threshold  $\epsilon = 0.05$  m -- the agent receives no useful gradient until it crosses the threshold. This is why sparse rewards create a needle-in-a-haystack exploration problem that standard algorithms like PPO cannot solve alone. (Generated by `bash docker/dev.sh python scripts/capture_proposal_figures.py reward-diagram.`)

## The critical invariant

Both reward checks verify the same fundamental property -- the *critical invariant* for the entire book:

The reward returned by `env.step()` must equal `env.unwrapped.compute_reward(achieved_goal, desired_goal, info)`.

We run these checks because different versions of gymnasium-robotics have had bugs affecting reward computation, and API changes have altered the signature of `compute_reward`. A quick verification ensures that your specific installation behaves correctly.

More importantly, this invariant is the foundation of Hindsight Experience Replay. When HER relabels a trajectory with a different goal, it calls `compute_reward` with the new goal to get the relabeled reward. If `compute_reward` disagrees with `env.step()`, HER trains on incorrect labels. The policy would learn from corrupted data, and training could fail silently -- no error, no crash, just a policy that does not work.

**Tip:** If you are ever unsure whether the reward invariant holds after upgrading gymnasium-robotics, run the quick check: `bash docker/dev.sh python scripts/labs/env_anatomy.py --verify`. The dense and sparse reward checks (components 4 and 5) specifically verify this invariant. It takes less than a minute and can save you days of debugging corrupted HER training.

## 2.6 Build It: Goal relabeling simulation

Everything we have built up to -- the dictionary observations, the separate achieved and desired goals, the `compute_reward` function -- converges here. We are going to do something that seems odd at first: call `compute_reward` with goals that the environment never set.

### Why relabeling matters

The problem with sparse rewards is simple: if the agent never reaches the goal, the reward is -1 at every step of every episode, which means there is no gradient signal pointing toward success. The agent has no way to distinguish between a near-miss (3 cm from the goal) and a complete failure (30 cm away), since both get reward -1.

Hindsight Experience Replay (HER), which we cover in depth in Chapter 5, solves this by asking: "You failed to reach the goal, but you *did* reach some position. What if that position had been the goal?" HER takes the `achieved_goal` from a failed trajectory and retroactively pretends it was the `desired_goal`. Then it recomputes the reward -- and because the agent actually reached that position, the recomputed reward is 0 (success).

For this to work, the environment must let us call `compute_reward` with arbitrary goals -- not just the goal that was originally set. Let's verify that this works:

### Simulating relabeling by hand

```
# Goal relabeling check
# (adapted from scripts/labs/env_anatomy.py:relabel_check)

def relabel_check(env_id="FetchReachDense-v4", n_goals=10,
                  seed=0, atol=1e-10):
    """Call compute_reward with arbitrary goals (HER simulation)."""
    env = gym.make(env_id)
    obs, info = env.reset(seed=seed)
    goal_sp = env.observation_space.spaces["desired_goal"]
    # Take one step to get a non-trivial achieved_goal
    obs, _, _, _, info = env.step(env.action_space.sample())
    ag = np.asarray(obs["achieved_goal"])
    reward_type = getattr(
        env.unwrapped, "reward_type", "dense")
    eps = float(env.unwrapped.distance_threshold)
    mismatches = 0
    for _ in range(n_goals):
        random_goal = goal_sp.sample()
        cr = float(
            env.unwrapped.compute_reward(ag, random_goal, info))
        dist = float(np.linalg.norm(ag - random_goal))
        expected = (-dist if reward_type == "dense"
```

```

        else (0.0 if dist <= eps else -1.0))
    if abs(cr - expected) > atol:
        mismatches += 1
env.close()
return {"n_goals": n_goals, "mismatches": mismatches}

```

Here is what this code does. It first takes a step to get a non-trivial achieved goal (the gripper moved somewhere), then samples 10 random goals from the goal space -- positions the environment never intended as targets. For each random goal, it calls `compute_reward` with the actual achieved goal and verifies that the returned reward matches the distance formula.

This is exactly what HER does, in miniature. The agent “failed” (it did not reach the original desired goal), but we can ask: “what would the reward have been if the goal were somewhere else?” And `compute_reward` gives us a correct answer.

**Checkpoint.** Over 10 random goals: zero mismatches. `compute_reward` correctly handles arbitrary goals -- not just the one the environment set. No errors, no NaN, no crashes.

This proves the key property for HER: **we can recompute rewards for any goal without re-running the simulation.**

## Why this works (and why it would not work everywhere)

The reason `compute_reward` accepts arbitrary goals is that the Fetch reward depends on the goal only through the distance  $\|g_a - g\|$ . The function does not need to access the physics state, the action history, or any internal simulation data -- it takes two 3D vectors and computes a distance, which is why relabeling is both cheap and exact.

Not all environments have this property. An environment where the reward depends on the trajectory (not just the endpoint), or where “success” requires a specific sequence of actions, would not support this kind of relabeling. An environment that returns flat observations with no goal separation does not expose the structure HER needs -- you would not know what “achieved goal” to relabel with, and you would have no function to recompute rewards for a different goal.

The Fetch interface was designed with HER in mind -- the dictionary observations, the separate goals, and the standalone `compute_reward` are all part of that design. The original HER paper (Andrychowicz et al., 2017) introduced these environments alongside the algorithm, specifically to provide a test bed where the relabeling mechanism works cleanly.

**Note:** For a full treatment of HER's mechanism and the conditions under which it applies, see Chapter 5. For now, the important takeaway is practical: you have verified with your own hands that the Fetch environment supports goal relabeling, and you know exactly what that means -- calling `compute_reward` with goals the environment never set, and getting correct rewards back.

## 2.7 Build It: Cross-environment comparison

So far we have focused on FetchReach. But the Fetch family includes Push, PickAndPlace, and Slide, and the interface generalizes across all of them -- with important differences in the details.

### How observations change across tasks

The key difference: environments with objects have larger observation vectors because they include the object's state (position, rotation, velocity).

```
# Cross-environment comparison
# (adapted from scripts/labs/env_anatomy.py:cross_env_compare)

def cross_env_compare(seed=0):
    """Compare obs dims across Reach, Push, PickAndPlace."""
    env_configs = {
        "FetchReach-v4": {"expected_obs_dim": 10,
                          "ag_is_grip": True},
        "FetchPush-v4": {"expected_obs_dim": 25,
                          "ag_is_grip": False},
        "FetchPickAndPlace-v4": {"expected_obs_dim": 25,
                                  "ag_is_grip": False},
    }
    results = {}
    for env_id, cfg in env_configs.items():
        env = gym.make(env_id)
        obs, _ = env.reset(seed=seed)
        obs_vec = np.asarray(obs["observation"])
        ag = np.asarray(obs["achieved_goal"])
        grip_pos = obs_vec[:3]
        ag_matches_grip = bool(np.allclose(ag, grip_pos))
        results[env_id] = {
            "obs_dim": obs_vec.shape[0],
            "ag_matches_grip": ag_matches_grip,
        }
        env.close()
    return results
```

**Checkpoint.** Expected output:

- FetchReach-v4: obs\_dim=10, ag\_matches\_grip=True
- FetchPush-v4: obs\_dim=25, ag\_matches\_grip=False
- FetchPickAndPlace-v4: obs\_dim=25, ag\_matches\_grip=False

For Push and PickAndPlace, achieved\_goal is the **object position**, not the gripper position. This is because the task goal is about where the object ends up, not where the gripper is. The gripper position is still available in obs["observation"][:3].

## The 25D observation for manipulation tasks

Environments with objects (Push, PickAndPlace) include 15 additional dimensions:

Index	Semantic	Source
0-2	Gripper position	<code>grip_pos</code>
3-5	Object position	<code>object_pos</code>
6-8	Object relative position (object - gripper)	<code>object_rel_pos</code>
9-10	Gripper finger positions	<code>gripper_state</code>
11-13	Object rotation (Euler angles)	<code>object_rot</code>
14-16	Object linear velocity (relative to gripper)	<code>object_velp</code>
17-19	Object angular velocity	<code>object_velr</code>
20-22	Gripper linear velocity	<code>grip_velp</code>
23-24	Gripper finger velocities	<code>gripper_vel</code>

The crucial thing to notice is that when `achieved_goal` changes from tracking the gripper (Reach) to tracking the object (Push, PickAndPlace), the goal-achievement mapping  $\phi$  changes accordingly --  $\phi(s)$  is the gripper position for Reach but the object position for Push. The environment handles this transparently, so you do not need to change your code. But you need to understand it, because it affects what "success" means: in Push, the agent succeeds when the *object* (not the gripper) is within 5 cm of the target.

## Uniform interface, changing semantics

Despite the dimension differences, the *interface* is identical across all Fetch environments:

Property	FetchReach	FetchPush	FetchPickAndPlace
<code>obs["observation"]</code> dim	10	25	25
<code>obs["achieved_goal"]</code> dim	3	3	3
<code>obs["desired_goal"]</code> dim	3	3	3
Action dim	4	4	4
<code>compute_reward</code> API	same	same	same
<code>distance_threshold</code>	0.05	0.05	0.05

This uniformity is what lets us develop algorithms on Reach (fast iteration, easy debugging) and then apply them to harder tasks. The same `MultiInputPolicy`, the same `compute_reward` invariant, the same HER relabeling -- all transfer directly. What changes is the task difficulty, not the interface.

In many RL domains, moving to a harder task means rewriting the environment wrapper, changing the observation preprocessing, and adjusting the reward function. In Fetch, you change one string -- the environment ID -- and everything else stays the same. The code that trains PPO on `FetchReachDense-v4` in Chapter 3 will train SAC on `FetchPush-v4` in Chapter 5 with no structural changes. The only differences will

be algorithmic (SAC instead of PPO, HER for goal relabeling) and in hyperparameters (more training steps for harder tasks).

## 2.8 Bridge: Manual inspection meets the production script

We have now inspected every major component of the Fetch environment by hand:

1. **Observations:** dictionary with three keys, shapes (10,), (3,), (3,) for Reach
2. **Actions:** 4D Cartesian deltas in [-1, 1], each axis produces movement in the expected direction
3. **Goals:** 3D Cartesian positions within the workspace;  $\phi$  maps states to achieved goals
4. **Dense reward:**  $-\|g_a - g_d\|$ , matches `compute_reward` and `env.step()`
5. **Sparse reward:** 0 if distance  $\leq 0.05$ , else -1, all three sources agree
6. **Relabeling:** `compute_reward` accepts arbitrary goals and returns correct rewards
7. **Cross-environment:** interface is uniform, observation dimensions and  $\phi$  change with task complexity

The production script `scripts/ch01_env_anatomy.py` automates the same core checks for a single Fetch environment (describe, reward-check with relabeling, and a random-policy baseline) and writes the results as JSON artifacts. For the cross-environment comparison and the side-by-side dense vs sparse walkthroughs, use the lab script (`scripts/labs/env_anatomy.py --verify`).

You can run the bridging proof to confirm that the manual lab code and the production script agree:

```
bash docker/dev.sh python scripts/labs/env_anatomy.py --bridge
```

Expected output:

```
Environment Anatomy -- Bridging Proof
```

```
=====
```

```
Env: FetchReachDense-v4, seed=42, steps=100
```

```
Relabeled goals per step: 5
```

```
Tolerance: atol=1e-10
```

```
Step reward checks:    100 steps, mismatches=0
```

```
Relabel reward checks: 500 checks, mismatches=0
```

```
[MATCH] All rewards match within atol=1e-10
```

```
  manual_reward == compute_reward == step_reward (100 steps)
```

```
  relabel_reward == -||ag - random_goal|| (500 checks)
```

```
[BRIDGE OK] Bridging proof passed
```

That gives us 100 steps with 5 relabeled goals per step, for 500 total reward checks -- and zero mismatches. The manual computation and the environment's `compute_reward` agree to within 1e-10 on every single check.

This bridging proof serves the same purpose as unit tests in software engineering: it confirms that your understanding (the manual computation) matches the implementation (the environment's API). When you run the production script in the next section and it reports "OK," you know exactly what "OK" means -- because you have done the same checks by hand.

In later chapters, the bridging proof will be more dramatic: in Chapter 3, you will compare your from-scratch PPO loss computation against SB3's internal implementation. In Chapter 4, you will compare SAC update targets. Here, the bridge is simpler -- reward computation is just a distance calculation -- but the principle is the same: we find it valuable to verify any pipeline by hand before relying on it.

## 2.9 Run It: The inspection pipeline

Now we run the full production inspection. The script `scripts/ch01_env_anatomy.py` automates these checks for a single environment, producing machine-readable JSON artifacts.

```
-----
EXPERIMENT CARD: Fetch Environment Inspection
-----
Algorithm:      None (inspection and verification only)
Environment:    FetchReachDense-v4 (default; override with --env-id)

Run command (full inspection):
  bash docker/dev.sh python scripts/ch01_env_anatomy.py all \
    --seed 0

Time:           < 2 min (CPU or GPU)

Checkpoint track:
  N/A (no training; all commands produce results in seconds)

Expected artifacts:
  results/ch01_env_describe.json
  results/ch01_random_metrics.json

Success criteria:
  ch01_env_describe.json exists, contains observation_space
    with keys: observation (shape [10]), achieved_goal (shape [3]),
    desired_goal (shape [3])
  reward-check prints "OK:" (zero mismatches across 500 steps)
  ch01_random_metrics.json exists, success_rate near 0.0-0.1,
    return_mean in [-25, -10] for dense, ep_len_mean == 50
-----
```

By default, `--env-id auto` chooses `FetchReachDense-v4` if it is available in your Gym registry. To inspect another task, pass an explicit ID (for example, `--env-id FetchReach-v4` or `--env-id FetchPush-v4`). If you run multiple inspections, also



override `--describe-out` and `--random-out` to avoid overwriting the default artifact paths.

## Running the pipeline

The `all` subcommand runs three inspection stages:

**Stage 1: Describe** (`describe`). Creates `results/ch01_env_describe.json` documenting the observation and action spaces. This is the machine-readable version of section 2.3.

**Stage 2: Reward check** (`reward-check`). Runs 500 steps of random actions, verifying the critical invariant at each step: `env.step()` reward matches `compute_reward()` matches the distance formula. Also tests relabeling with random goals. This is the automated version of sections 2.5 and 2.6.

**Stage 3: Random episodes** (`random-episodes`). Runs 10 complete episodes with a random policy and records baseline metrics: success rate, mean return, mean episode length, and final goal distance. This establishes the performance floor.

## Interpreting the artifacts

`results/ch01_env_describe.json` contains the observation and action space schema. Open it and verify:

- `observation_space.observation.shape == [10]`
- `observation_space.achieved_goal.shape == [3]`
- `observation_space.desired_goal.shape == [3]`
- `action_space.shape == [4]`
- `action_space.low == [-1, -1, -1, -1]`
- `action_space.high == [1, 1, 1, 1]`

`results/ch01_random_metrics.json` contains the random baseline. Expected values for FetchReachDense-v4:

Metric	Expected range	Meaning
<code>success_rate</code>	0.0-0.1	Random actions very rarely reach the goal
<code>return_mean</code>	-25 to -10	Sum of negative distances over 50 steps
<code>ep_len_mean</code>	50	Episodes always run to the truncation limit
<code>final_distance_mean</code>	0.05-0.15	Average distance to goal at episode end

These baseline numbers are your floor. In Chapter 3, PPO must produce a success rate well above 0.1 and a return much closer to 0. If a trained policy's metrics are not clearly better than these random baseline values, something is wrong with training.

## The random baseline as diagnostic tool

The random baseline is more useful than it might appear. It answers a concrete question: "how hard is this task for an agent that does nothing intelligent?" If random

success rate is already 20-30%, the task might be too easy to test your algorithm. If it is 0.0% over hundreds of episodes, the task is genuinely hard -- the agent must learn something specific to succeed.

For FetchReachDense-v4 with a threshold of 0.05 meters, random success is typically 0-10%. The workspace is much larger than the success region, so stumbling into the goal by chance is rare but not impossible. This makes Reach a good development environment: hard enough that random does not solve it, easy enough that basic algorithms (PPO with dense rewards) reliably learn it.

Note the `ep_len_mean` of 50, which confirms something we mentioned in section 2.2: episodes are truncated at 50 steps, never terminated early, so even when the agent reaches the goal the episode continues. This is a design choice in the Fetch environments -- the agent is rewarded for staying at the goal, not just reaching it. For dense rewards, staying at the goal produces rewards near 0 (distance near 0), which is the maximum possible. For sparse rewards, staying at the goal produces reward 0 (success), which is also the maximum. Both reward structures incentivize reaching and holding the goal position.

## 2.10 What can go wrong

Here are the most common issues when inspecting Fetch environments, along with diagnostics. We have encountered all of these during development.

### **obs is a flat array, not a dictionary**

**Symptom.** `type(obs)` is `ndarray`, not `dict`. Calling `obs["observation"]` raises `TypeError`.

**Cause.** Old version of `gymnasium-robotics` (before 1.0), wrong environment ID, or a wrapper that flattens the dictionary.

**Fix.** Run `pip show gymnasium-robotics` and check the version is `>= 1.0`. Verify the environment ID matches a known Fetch environment. If you are wrapping the environment with SB3's `FlattenObservation`, remove that wrapper -- goal-conditioned environments must keep the dictionary structure.

### **obs["observation"] shape is not (10,) for FetchReach**

**Symptom.** The observation has 25 dimensions instead of 10 (or some other unexpected number).

**Cause.** You are using `FetchPush` or `FetchPickAndPlace` (which have 25D observations), or there is a version mismatch.

**Fix.** Print `env.spec.id` to confirm the environment ID. Check `env.observation_space` for the full structure.

### **compute\_reward raises AttributeError**

**Symptom.** `env.compute_reward(...)` fails with `AttributeError: 'TimeLimit' object has no attribute 'compute_reward'`.

**Cause.** Calling on the wrapped environment instead of the unwrapped base environment. `gym.make()` wraps environments in `TimeLimit` and other wrappers that do not expose `compute_reward`.

**Fix.** Use `env.unwrapped.compute_reward(ag, dg, info)`.

### **Step reward and compute\_reward disagree**

**Symptom.** The three-way comparison shows mismatches. `Manual reward`, `compute_reward`, and `env.step()` return different values.

**Cause.** Version mismatch between `gymnasium` and `gymnasium-robotics`. Some versions changed the reward computation or the `compute_reward` API.

**Fix.** Upgrade both packages: `pip install --upgrade gymnasium gymnasium-robotics`. Then re-run the verification.

### **desired\_goal is identical across resets**

**Symptom.** Every call to `env.reset()` returns the same `desired_goal`.

**Cause.** Not passing different seeds, or passing the same seed every time.

**Fix.** Pass unique seeds: `env.reset(seed=42 + episode_number)`. If you want truly random goals, omit the seed argument.

### **achieved\_goal does not match obs["observation"][:3] for FetchPush**

**Symptom.** For `FetchPush`, `np.allclose(obs["achieved_goal"], obs["observation"][:3])` returns `False`.

**Cause.** This is correct behavior, not a bug. For `Push` and `PickAndPlace`, `achieved_goal` is the **object** position, not the gripper position. The gripper position is `obs["observation"][:3]`, but the goal is about where the object ends up.

**Fix.** No fix needed -- this is by design. See section 2.7 for the explanation.

### **EnvironmentNameNotFound for FetchReachDense-v4**

**Symptom.** `gym.make("FetchReachDense-v4")` raises `gymnasium.error.NameNotFound`.

**Cause.** `gymnasium-robotics` is not installed, or the version does not include v4 environments.

**Fix.** Install with `pip install gymnasium-robotics`. If installed but v4 is not found, check the version -- v4 environments were introduced in `gymnasium-robotics 1.2.0`.

## Random success rate much higher than 0.1

**Symptom.** Running 100 random episodes gives `success_rate` of 0.3 or higher.

**Cause.** The distance threshold might be larger than expected, or the goal space might be very small.

**Fix.** Check `env.unwrapped.distance_threshold` -- it should be 0.05. If it is different, your environment version uses a different default.

## `is_success` is True immediately after reset

**Symptom.** The very first step of an episode reports `is_success: True` in the `info` dict, or the sparse reward is 0 right after reset.

**Cause.** The desired goal happened to be sampled at (or very near) the gripper's initial position. This is rare but normal -- it occurs in fewer than 5% of episodes.

**Fix.** No fix needed. Run multiple episodes and verify that success at reset is rare. If it happens consistently (every episode), there is likely a bug in goal sampling -- check that you are passing different seeds to `env.reset()`.

## Workspace bounds look wrong

**Symptom.** Goal positions are near (0, 0, 0) or have very large values.

**Cause.** Different MuJoCo model version or coordinate frame issue.

**Fix.** Check `env.unwrapped.initial_gripper_xpos` -- typical values are around [1.34, 0.75, 0.53]. If these are very different, the MuJoCo model may have been modified or replaced.

## 2.11 Summary

You now understand the Fetch environment interface at the level needed to train and debug policies. Specifically:

- **Observations** are dictionaries with three keys: `observation` (proprioceptive state, 10D for Reach, 25D for Push/PickAndPlace), `achieved_goal` (where you are, 3D), and `desired_goal` (where you should be, 3D). This structure is what makes goal-conditioned learning explicit.
- **Actions** are 4D Cartesian deltas in [-1, 1]: three components for end-effector movement (dx, dy, dz) and one for gripper control. The agent operates in Cartesian space; an internal controller handles inverse kinematics.
- **Dense rewards** equal  $-\|g_a - g_d\|$  -- negative distance. **Sparse rewards** are 0 if distance  $\leq 0.05$ , else -1. Both can be recomputed for arbitrary goals via `compute_reward`.
- **The critical invariant** -- `env.step()` reward equals `compute_reward(ag, dg, info)` -- holds for all Fetch environments and is the foundation of HER.

- **Goal relabeling works:** calling `compute_reward` with goals the environment never set produces correct rewards, enabling the “what if that had been the goal?” trick at the core of HER.
- **The interface is uniform across Fetch tasks:** same dictionary structure, same action space, same `compute_reward` API. What changes is the observation dimension and what `achieved_goal` tracks (gripper for Reach, object for Push/PickAndPlace).
- **The random baseline** (success\_rate 0.0-0.1, return\_mean in [-25, -10] for dense Reach) is the performance floor that any trained agent must beat.

With this anatomy understood, Chapter 3 trains a real policy. PPO on FetchReachDense-v4 will use the observation shapes you documented here to build its network, the reward signal you verified to drive learning, and the random baseline you established as the metric it must surpass.

---

## Verify It

VERIFY IT (Chapter 2)

Run command:

```
bash docker/dev.sh python scripts/ch01_env_anatomy.py all --seed 0
```

Hardware: Any machine with Docker (no GPU required)

Time: < 2 min

Artifacts:

```
results/ch01_env_describe.json
results/ch01_random_metrics.json
```

Expected highlights (FetchReachDense-v4):

```
describe: observation [10], achieved_goal [3], desired_goal [3], action [4], bound
reward-check: OK: reward checks passed (atol=1e-6, n_steps=500, n_random_goals=3)
random-episodes (10): success_rate 0.0-0.1, return_mean -25 to -10, ep_len_mean !
```

Optional lab checks:

```
bash docker/dev.sh python scripts/labs/env_anatomy.py --verify
bash docker/dev.sh python scripts/labs/env_anatomy.py --bridge
```

## Exercises

### 1. (Verify) Confirm observation structure across seeds.

Reset FetchReachDense-v4 with 5 different seeds. For each reset, verify that the observation dictionary has the same three keys and the same shapes. Record the range of `desired_goal` values across resets.

Expected: goals span the workspace (roughly  $x$  1.1-1.5,  $y$  0.5-1.0,  $z$  0.35-0.75). If all goals are identical, something is wrong with the seed handling -- check that you are passing different seeds to each `env.reset()` call.

## 2. (Tweak) Compare dense and sparse rewards on the same trajectory.

Create both `FetchReachDense-v4` and `FetchReach-v4` with the same seed. Take the same sequence of 50 random actions in both. Compare the reward sequences side by side. Questions:

- (a) Is the dense return always more negative than the sparse return?
- (b) What fraction of steps have sparse reward = 0?
- (c) At what distance does the sparse reward switch from -1 to 0?

Expected: sparse reward is 0 only when distance < 0.05. Dense return is typically -25 to -10; sparse return is typically -50 (all -1s, since random actions rarely reach the goal).

## 3. (Extend) Observation breakdown for FetchPush.

Create `FetchPushDense-v4` and inspect the 25D observation vector. Using the observation component table from section 2.7, identify:

- (a) Which indices correspond to the object position
- (b) What `achieved_goal` represents (hint: it is the object position, not the gripper position)
- (c) What happens to the object position when you take action `[0, 0, 0, 0]` for 50 steps -- does the object move?

Expected: the object stays roughly in place (gravity keeps it on the table); `achieved_goal` tracks the object, not the gripper.

## 4. (Challenge) Estimate success rate as a function of distance threshold.

Run 100 random episodes on `FetchReachDense-v4`. For each episode, record the final distance between `achieved_goal` and `desired_goal`. Then tabulate what the success rate *would be* at thresholds of 0.01, 0.02, 0.05, 0.10, and 0.20 meters. How does the "difficulty" of the task change with the threshold?

Expected: at threshold 0.01, random success is roughly 0%; at 0.20, it may be 5-15%. The default threshold of 0.05 makes random success very rare (0-5%). This exercise gives you intuition for how the success threshold determines task difficulty -- a concept we revisit when discussing sparse rewards in Chapter 5.