Lecture 4: Model-free RL (Part I)

Lei Zhang

Outline

- Monte Carlo Prediction
- Monte Carlo Control
- Extensions: on- and off-policy learning

*Materials are modified from David Silver's RL lecture notes

Outline

- Monte Carlo Prediction
- Monte Carlo Control
- Extensions: on- and off-policy learning

Monte Carlo RL

- MC methods learn directly from episodes of experience
- MC is *model-free*: no knowledge of MDP transitions / rewards
- MC learns from *complete* episodes: no bootstrapping
- MC uses the simplest possible idea: value = mean return
- Caveat: can only apply MC to *episodic* MDPs
    - All episodes must terminate

MC Policy Evaluation

- Goal: learn v_π from episodes of experience under policy π

$$S_1, A_1, R_2, ..., S_k \sim \pi$$

- Recall that the *return* is the total discounted reward:

$$G_t = R_{t+1} + \gamma R_{t+2} + ... + \gamma^{T-1} R_T$$

- Recall that the value function is the expected return:

$$v_\pi(s) = \mathbb{E}_\pi \left[G_t \mid S_t = s \right]$$

- Monte-Carlo policy evaluation uses *empirical mean* return instead of *expected* return

First Visit MC Policy Evaluation

- To evaluate state s
- The first time-step t that state s is visited in an episode,
- Increment counter $N(s) \leftarrow N(s) + 1$
- Increment total return $S(s) \leftarrow S(s) + G_t$
- Value is estimated by mean return $V(s) = S(s)/N(s)$

  By law of large numbers, $V(s) \rightarrow v_\pi(s)$ as $N(s) \rightarrow \infty$

Every Visit MC Policy Evaluation

- To evaluate state s
- Every time-step t that state s is visited in an episode,
- Increment counter $N(s) \leftarrow N(s) + 1$
- Increment total return $S(s) \leftarrow S(s) + G_t$
- Value is estimated by mean return $V(s) = S(s)/N(s)$

  Again, $V(s) \rightarrow v_\pi(s)$ as $N(s) \rightarrow \infty$

Incremental Mean

The mean $\mu_1, \mu_2, ...$ of a sequence $x_1, x_2, ...$ can be computed incrementally,

$$\begin{aligned}
\mu_k &= \frac{1}{k} \sum_{j=1}^{k} x_j \\
&= \frac{1}{k} \left(x_k + \sum_{j=1}^{k-1} x_j \right) \\
&= \frac{1}{k} \left(x_k + (k-1)\mu_{k-1} \right) \\
&= \mu_{k-1} + \frac{1}{k} \left(x_k - \mu_{k-1} \right)
\end{aligned}$$

Incremental MC Updates

- Update $V(s)$ incrementally after episode $S_1, A_1, R_2, ..., S_T$
  For each state S_t with return G_t

$$N(S_t) \leftarrow N(S_t) + 1$$

$$V(S_t) \leftarrow V(S_t) + \frac{1}{N(S_t)} \left(G_t - V(S_t) \right)$$

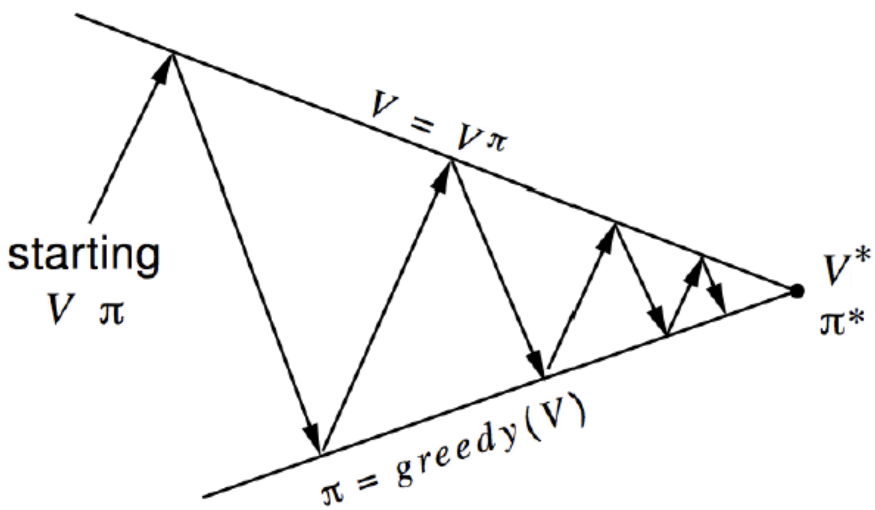
- In non-stationary problems, it can be useful to track a running mean, i.e. forget old episodes.

$$V(S_t) \leftarrow V(S_t) + \alpha \left(G_t - V(S_t) \right)$$

Outline

- Monte Carlo Prediction
- Monte Carlo Control
- Extensions: on- and off-policy learning

Generalized Policy Iteration (GPI) Revisited

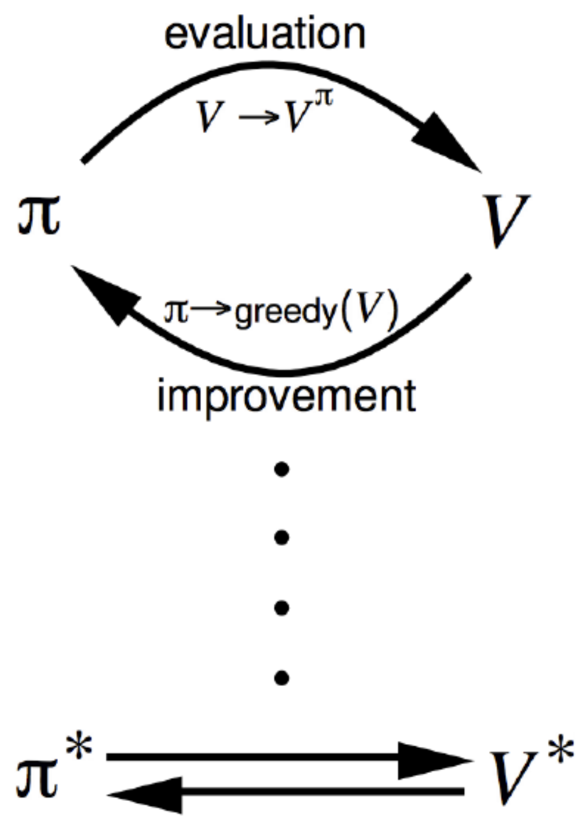


Policy evaluation Estimate v_π

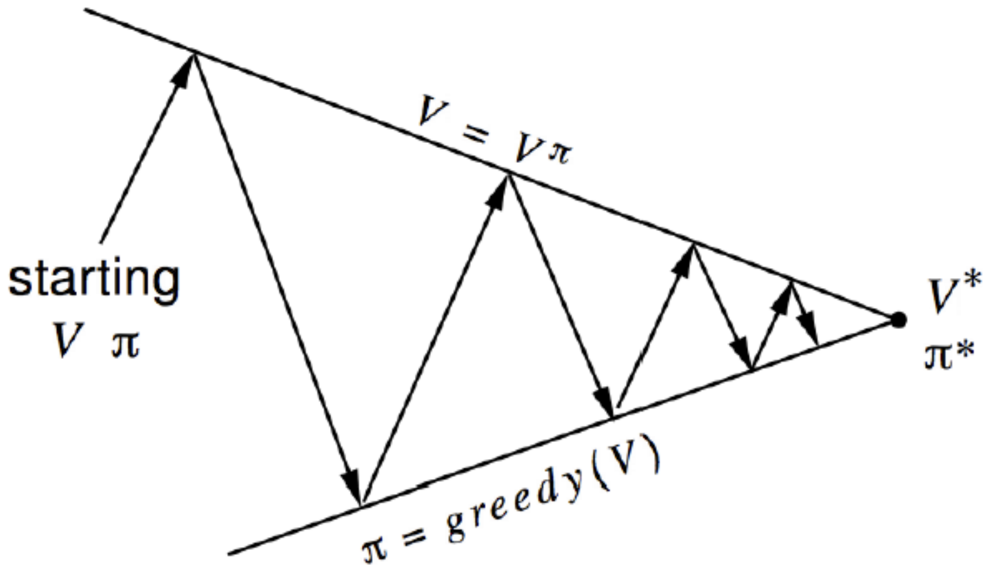
e.g. Iterative policy evaluation

Policy improvement Generate $\pi' \geq \pi$

e.g. Greedy policy improvement



GPI with MC Evaluation



Policy evaluation Monte-Carlo policy evaluation, $V = v_\pi$?

Policy improvement Greedy policy improvement?

Model Free GPI with MC Evaluation

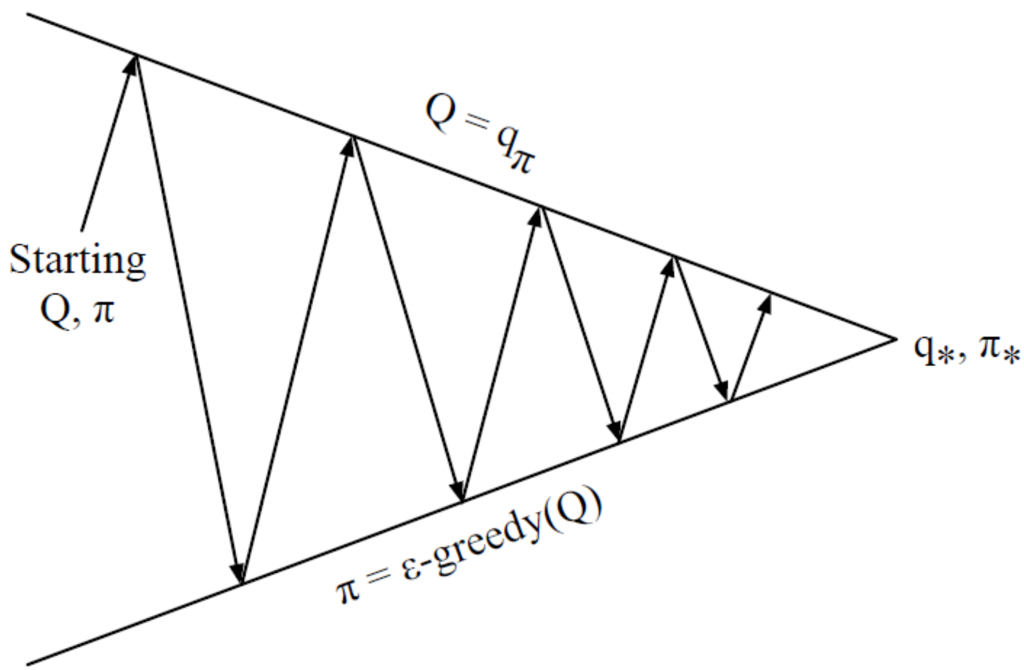
- Greedy policy improvement over $V(s)$ requires model of MDP

$$\pi'(s) = \underset{a \in \mathcal{A}}{\operatorname{argmax}}\ \mathcal{R}_s^a + \mathcal{P}_{ss'}^a V(s')$$

- Greedy policy improvement over $Q(s, a)$ is model-free

$$\pi'(s) = \underset{a \in \mathcal{A}}{\operatorname{argmax}}\ Q(s, a)$$

MC Policy Iteration



Policy evaluation Monte-Carlo policy evaluation, $Q = q_\pi$

Policy improvement ϵ-greedy policy improvement

GLIE Condition for Policies

Greedy in the Limit with Infinite Exploration (GLIE)

All state-action pairs are explored infinitely many times,

$$\lim_{k \to \infty} N_k(s, a) = \infty$$

The policy converges on a greedy policy,

$$\lim_{k \to \infty} \pi_k(a|s) = \mathbf{1}(a = \underset{a' \in \mathcal{A}}{\operatorname{argmax}} \; Q_k(s, a'))$$

For example, ϵ-greedy is GLIE if ϵ reduces to zero at $\epsilon_k = \frac{1}{k}$

GLIE MC Policy Iteration

- Sample kth episode using π: $\{S_1, A_1, R_2, ..., S_T\} \sim \pi$
- For each state S_t and action A_t in the episode,

$$N(S_t, A_t) \leftarrow N(S_t, A_t) + 1$$

$$Q(S_t, A_t) \leftarrow Q(S_t, A_t) + \frac{1}{N(S_t, A_t)} (G_t - Q(S_t, A_t))$$

- Improve policy based on new action-value function

$$\epsilon \leftarrow 1/k$$

$$\pi \leftarrow \epsilon\text{-greedy}(Q)$$

GLIE Monte-Carlo control converges to the optimal action-value function, $Q(s, a) \rightarrow q_*(s, a)$

Outline

- Monte Carlo Prediction
- Monte Carlo Control
- Extensions: on- and off-policy learning

On- and Off-Policy

- On-policy learning

  "Learn on the job"

  Learn about policy π from experience sampled from π

- Off-policy learning

  "Look over someone's shoulder"

  Learn about policy π from experience sampled from μ

Important Sampling

- Estimate the expectation of a different distribution

$$
\begin{aligned}
\mathbb{E}_{X\sim P}[f(X)] &= \sum P(X)f(X) \\
&= \sum Q(X)\frac{P(X)}{Q(X)}f(X) \\
&= \mathbb{E}_{X\sim Q}\left[\frac{P(X)}{Q(X)}f(X)\right]
\end{aligned}
$$

Important Sampling in MC Policy Iteration

- Use returns generated from μ to evaluate π
- Weight return G_t according to similarity between policies
- Multiply importance sampling corrections along whole episode

$$G_t^{\pi/\mu} = \frac{\pi(A_t|S_t)}{\mu(A_t|S_t)} \frac{\pi(A_{t+1}|S_{t+1})}{\mu(A_{t+1}|S_{t+1})} \dots \frac{\pi(A_T|S_T)}{\mu(A_T|S_T)} G_t$$

- Update value towards *corrected* return

$$Q(S_t, A_t) \leftarrow Q(S_t, A_t) + \frac{1}{N(S_t, A_t)} \left(\boxed{G_t} - Q(S_t, A_t) \right)$$

- Cannot use if μ is zero when π is non-zero
- Importance sampling can dramatically increase variance