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Fluents valuation in Deep Reinforcement Learning and logic for temporal goals

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Contents

1	Introduction	1
1.1	Reinforcement Learning in games	1
1.2	Objective of this work	3
1.3	Structure of the thesis	4
2	Guiding agents with temporal logics	5
2.1	Temporal logics and Linear Dynamic Logic	5
2.1.1	Temporal logics on finite traces	5
2.1.2	Linear Dynamic Logic	6
2.2	Reinforcement learning with restraining specifications	8
3	Learning to valueate fluents in games	9
3.1	Temporal constraints	9
3.2	Assumptions	9
3.3	General structure of the model	9
3.4	Encoding	9
3.4.1	Model: Deep Belief Network	10
3.4.2	What does it learn	10
3.5	Boolean functions	10
3.5.1	Learning with genetic algorithms	10
3.5.2	Boolean rules	10
4	AtariEyes package	11
4.1	How to use the software	11
4.1.1	Tools and setup	11
4.1.2	Commands	11
4.2	Implementation	11
4.2.1	<code>agent</code> Module	11
4.2.2	<code>streaming</code> Module	11
4.2.3	<code>features</code> Module	11
5	Experiments	13
5.1	Breakout	13
5.1.1	Definitions	13
5.1.2	Training	13
5.1.3	Comments	13
5.2	Montezuma's Revenge	13

5.2.1	Definitions	13
5.2.2	Training	13
5.2.3	Comments	13
5.3	New example	13
6	Conclusions and future work	15

Chapter 1

Introduction

In Artificial Intelligence (AI), among the many approaches for building intelligent agents, we can distinguish those mainly focused on knowledge and planning, and those that mainly try out different actions to discover the goodness of their outcomes. With the former, we refer to those developed from *classical planning*, while the latter is the recently-successful field of *reinforcement learning*. While they can be integrated, they use quite different techniques. However, they share a common basic need: the agent must be able to perceive meaningful events happening in the outside world.

In planning, in almost every practical case, there is some form of partial observability or nondeterminism. So, agent's observations become essential [20]. Observing, however, does not simply refer to reading a raw input from the sensor. Instead, it means “grounding” all symbols that compose the abstraction the agent adopts: essentially, all symbols representing conditions which happen to be true in the environment, should become true for the agent. We refer to these symbols with the term *fluents*. Fluents are atomic propositions can change in time, whose valuation should always reflect the current state of the world.

We could argue that reinforcement learning does not require such valuations. Still, rewards and punishments must be somehow supplied in response to desirable and undesirable events. We could think of providing these feedbacks with programmed ad-hoc conditions, but this can be done just for the simulations we create. As we will see, when the agent needs a component that is based on logic and reasoning, we still need to value the truth of fluents, even in the context of reinforcement learning. In fact, the most successful approaches mix these components somehow.

This thesis addresses the problem of valuating fluents from complex observations of the environment. However, this is a general topic and we'll only work with specific classes of fluents and observations. Every choice or assumption that restricts the applicability of this method will be pointed out along the text. The first distinction to do is that we'll only work with games.

1.1 Reinforcement Learning in games

Games in AI are a class static environments with discrete actions. They have always been a classic benchmark for AI, because they provide various levels of complexity,

they have few and strict rules and are easy to implement and simulate.

Reinforcement learning (RL) is a field of AI that has shown to be successful for many games. This is the learning method adopted here. In RL, the agent tries out different actions and observes the reward received. Its goal is to learn the optimal policy, the one maximizing the cumulative reward over the whole episode. Most RL algorithms assume that observations and rewards can be modelled with a Markov Decision Process (MDP). This means that: the sequence of states create a Markov chain (the next state only depends on the previous state and action); the rewards only depend on the current state; the observations are an exact representation of the current state. Many learning algorithms exist for this setting [21].

Neural Networks (NN) have brought new possibilities for RL: in Deep Reinforcement Learning, the agent employs a neural network as a very expressive approximation to the quantities it is trying to learn [8]. The Q-value, for example, is a classic quantity in RL that estimates the expected cumulative reward from each pair of observation and action. A Deep Q-Network (DQN) is able to learn this estimate for a complex observation such as the frame of a video game, which is a high-dimensional input [17] that would be hard to manage without neural networks.

All models and experiments in this thesis use games from the Atari 2600 collection. The framework adopted is an interface for the Atari simulator [2] that maps actions to controller inputs and returns images of the game as observations. This is almost the same condition a human player faces when playing the same games. Other successful works also read the current number of lives the player has. Other than that, no internals are employed to simplify the task of the agent.

The reinforcement learning algorithm adopted in this thesis is a deep variant of Double DQN that solves few issues with simple DQN [24]. The motivation of this choice is that this is a relatively simple algorithm, based on DQN, which has also proven to be successful for the specific environments that we'll use in our experiments [16]. In fact, among Q-Network algorithms, the only ones that clearly achieve superior performances in most games adopt a combination of all variants [12].

Not all games inside the Atari 2600 collection are equally hard to solve. Reinforcement learning agents can be trained to achieve higher performances with respect to an average human player, mostly for environments with static map and background, and simple strategies. Many other games, instead, require the agent to remember previous steps and observations, for example, in exploration tasks. One notable example is *Montezuma's Revenge*, in which agents could not improve in any way [16]. Other approaches could succeed in this game with additional information able to guide the agent. For example, with carefully chosen initializations and examples from human experts [15].

One issue with games like *Montezuma's Revenge*, is that they require long sequences of correct actions before rewarding the agent. This is called a *sparse reward*. However, there is a more fundamental problem to be considered first: observations and rewards, together, can't define a Markov Decision Process, because it is essential for the agent to remember some informations collected during the game. For example, the *Montezuma's* agent may walk to the right only if it *remembers* that the door in the right room has been previously opened. This additional ability is required because of partial observations: a view of the current room can't be considered a complete state of the game, sufficient to predict future rewards.

The setting just described can be modelled with a Non-Markovian Reward Decision Process (NMRDP). Fortunately, it is possible to cast any NMRDP as a MDP, if enough information about the history is included in each observation. In order to render this transformation feasible, we must include as few additional data as possible, still with an exhaustive state with respect to the reward. As humans, we understand which sequences lead to rewards. So, an elegant way to do this, is to declare such sequences with *temporal logics* [1]. As we will see, by tracking the satisfaction of such temporal formula, we can provide enough information to the agent so to employ standard algorithms developed for MDPs [3][6].

This type of construction can be considered as a “logic component” inside the agent, as we’ve previously called it. While an abstraction like this is powerful, it is essential to correctly value the symbols it uses, in order to reason about the current situation. This is a complex task for environments with rich observations, as those allowed by Deep Reinforcement Learning.

1.2 Objective of this work

The main purpose of this work is to devise and test a mechanism able to learn functions which valuates the fluents we define. Specifically, learn a function that computes the truth value for a set of boolean conditions, given a frame of an Atari game. Among the many different ways to accomplish this, the most interesting techniques are those which pose the least number of assumptions on the specific environment. In this respect, the following are important achievements of this work to be highlighted:

- Fluents are selected first. Then, the function to evaluate them is trained from a description of each fluent. This is harder to do than just training a features extractor and manually trying to associate a meaning to each feature.
- To describe the fluents we use temporal logic over finite traces such as LTL_f and LDL_f . These are employed as tools to formalize any type of temporal constraints the fluents are always expected to satisfy. The use of such logics for this purpose can be a really generic approach. This thesis is an initial investigation about this possibility. As a description of a fluent, we must consider everything that guides the training process. So, we will certainly consider other types of hints that is useful to include, such as visual hints.
- The training algorithm won’t require any manual annotation, nor labelled datasets at all. The main idea is that, inside the agent, two components should coexist: the player and the observer. While the player explores the environment, the observer can be trained from the images received, without further intervention.

The second goal of this thesis is to demonstrate how such trained features can be exploited by a Reinforcement Learning agent to solve hard games. Tests will be conducted on Montezuma’s Revenge, a game known to be difficult in this class [16]. In this thesis:

- We provide a flexible implementation of the construction described in [3][6], for temporal goals.
- A deep agent architecture is proposed to merge the technique above for the Deep Reinforcement Learning case.
- This implementation is then used to specify a temporal goal in LDL_f , sufficient to guide the agent through hard environments.

1.3 Structure of the thesis

Chapter 2

Guiding agents with temporal logics

As pointed out in the introduction, the hardest games cannot be solved with a pure application of Deep Reinforcement Learning alone. Some complex tasks can be completed only with long sequences of correct actions, without any observable advancement in the environment to be tracked. An agent based on the Markov assumption, which purely associates observations to actions and lacks any form of memory, cannot accomplish such tasks. In this chapter, we will review an elegant method to add this capability to a RL agent [1][3].

Before explaining how to guide the agent in its task, it's necessary to first understand how to *declare* the desired behaviour. Temporal logics are a class of formal systems that allow to talk about properties that change over time. So, we will review them first. Since the construction presented here transforms such logic description, this part is an important step toward the desired solution.

When thinking about desired behaviours, we can't talk about actions, as this is a too specific level of description, and the optimal sequence of actions is always unknown. A very convenient level of abstraction is given by the evolution of some interesting fluents we have defined. Fluents are Boolean atomic propositions that reflect the current state of the environment. So, we're effectively talking about trajectories of the environment, not the agent's. Together, they also compose an excellent abstraction, because they can be selected to represent the conditions we consider as relevant. Examples for games are: "the enemy is dead", "I have 4 lives remaining", "I am in the first room", etc.

What has been called "behaviour" or "high-level plan" is simply the set of desired evolutions of such symbols. Temporal logics are the perfect formalism to select such sequences among all the possible ones.

2.1 Temporal logics and Linear Dynamic Logic

2.1.1 Temporal logics on finite traces

Temporal logics are a class of formal languages, more precisely modal logics, that allow to talk about time [10]. Among all formalisms, we care about logics that

assume a linear time, as opposed to branching, and a discrete sequence of instants, instead of continuous time. In computer science, the most famous logic in this group is the Pnueli’s Linear Temporal Logic (LTL) [19].

The assumptions about the nature of time directly reflect to the type of structures these logics are interpreted on: their models are $\mathcal{M} = \langle T, \prec, V \rangle$, where the set T is a discrete set of time instants, such as \mathbb{N} , and \prec is a complete ordering relation on T , like $<$. If a logic defines a set \mathcal{F} of atomic propositions, the evaluation function $V : T \times \mathcal{F} \rightarrow \{\text{true}, \text{false}\}$, for each instant of time, assigns a truth value to each fluent. An equivalent and compact way of defining such structures is with *traces*. A trace π is a sequence of propositional interpretations $2^{\mathcal{F}}$ of the fluents \mathcal{F} . Each element of the trace, $\pi(i)$, is the set of true symbols at time i . $\pi(i, j)$ represents the trace between instants i and j .

LTL is a logic that only allows to talk about the future. The semantic of its temporal operators, *neXt* \bigcirc , *Until* \mathcal{U} , and of those derived, eventually \Diamond , always \Box , can only access future instants on the sequence. Interpretations for this logic are infinite traces with a first instant, which are equivalent to valuations on the temporal frame $\langle \mathbb{N}, < \rangle$.

As it has been pointed out [4], most practical uses of LTL interpret the formulae on *finite* traces, not infinite. The pure existence of a last instant of time has strong consequences on the meaning of the operators, because they need to handle such instant differently. The Always operator \Box , translates to “until the last instant”, quite naturally. However, writing $\Box\Diamond\varphi$ does not require that φ becomes true an infinite number of times, that is the “response” property; instead, it is satisfied exactly by those traces in which φ is true at *Last* (*Last* is an abbreviation for $\neg\bigcirc\text{true}$ and it evaluates to true at last instant only). Furthermore $\Box\Diamond\varphi$ and $\Diamond\Box\varphi$ are both equivalent to $\Diamond(\text{Last} \wedge \varphi)$, something that doesn’t happen in standard LTL. From last example, it should be clear that the expressive power of the language has changed and LTL interpreted over finite traces should be regarded as a different logic, that we denote with LTL_f . More precisely, over infinite linearly-ordered interpretations, LTL has the same expressive power of Monadic Second Order Logic (MSO), while LTL_f is equivalent to First-Order Logic (FOL) and star-free regular expressions, which are strictly less expressive.

In the next section, we will define a temporal logic, called LDL_f , that is purposefully devised for finite traces. This is the formalism that we use in the implemented construction for RL agents. However, many plans and behaviours to be rewarded can be also expressed with LTL_f . So, for this construction, any temporal logic over finite traces which can be translated to equivalent finite-state automata can be used as an alternative to LDL_f ; even temporal logics of the past [1].

2.1.2 Linear Dynamic Logic

In this section, we will define Linear Dynamic Logic of finite traces (LDL_f) [4]. Its syntax combines regular expressions and propositional logic, just like Propositional Dynamic Logic (PDL) does [7][23]. So, we will review regular expressions first.

Regular Temporal Specifications

Regular languages are the class of languages exactly recognized by finite state automata and regular expressions [13]. So, we will use regular expressions as a compact formalism to specify them. Regular expressions are usually said to accept strings. Traces are in fact strings, whose symbols $s \in 2^{\mathcal{F}}$ are propositional interpretations of the fluents \mathcal{F} . Such regular expressions would be:

$$\rho ::= \emptyset \mid s \mid \rho_1 + \rho_2 \mid \rho_1; \rho_2 \mid \rho^* \quad (2.1)$$

where \emptyset denotes the empty language, $s \in 2^{\mathcal{F}}$ is a symbol, $+$ is the disjunction of two constraints, $;$ separates concatenated expressions, and ρ^* requires an arbitrary repetition on ρ . Parentheses can be used to group expressions with any precedence.

We call the regular expressions of equation (2.1) Regular Temporal Specifications RE_f , because they are interpreted on finite linear temporal structures. However, writing specifications in terms of single interpretations is very cumbersome. So, we substitute the symbols $s \in 2^{\mathcal{F}}$ with formulae of Propositional Logic. A propositional formula ϕ represents all interpretations that satisfy it: $\text{Sat}(\phi) = \{s \in 2^{\mathcal{F}} \mid s \models \phi\}$.

The new definition for the syntax of Regular Temporal Specifications RE_f :

$$\rho ::= \phi \mid \rho_1 + \rho_2 \mid \rho_1; \rho_2 \mid \rho^* \quad (2.2)$$

where ϕ is a propositional formula on the set of atomic symbols \mathcal{F} . The language generated by a RE_f ρ , denoted $\mathcal{L}(\rho)$, is the set of traces that match the temporal specification. The only difference with regular expressions' standard semantics is that a symbol $s \in 2^{\mathcal{F}}$ matches a propositional formula ϕ if and only if $s \in \text{Sat}(\phi)$. A trace that match the regular expression $\pi \in \mathcal{L}(\rho)$ is said to be generated or accepted by the specification ρ .

Example. As an example, let's define a RE_f expression $\rho := \text{true}; (\neg B)^*; (A \wedge B)$ and the following traces:

$$\begin{aligned} \pi_1 &:= \langle \{\}; \{A\}; \{A\}; \{A, B\} \rangle \\ \pi_2 &:= \langle \{B\}; \{A, B\} \rangle \\ \pi_3 &:= \langle \{A, B\}; \{B\}; \{B\} \rangle \end{aligned}$$

The first two traces are accepted by the expression, $\pi_1, \pi_2 \in \mathcal{L}(\rho)$, but the third is not, $\pi_3 \notin \mathcal{L}(\rho)$. Of course, the symbols A and B could represent any meaningful property of the environment to be ensured.

Linear Dynamic Logic

Linear Dynamic Logic is a temporal logic for finite traces that was first defined in [4]. The definition we see here, also adopted by the implementation we'll use, is a small variant that can also be interpreted over the empty trace, $\pi_\epsilon = \langle \rangle$, unlike most logics that assume a non-empty temporal domain T .

Definition. A LDL_f formula φ is built as follows:

$$\begin{aligned}\varphi &::= tt \mid \neg\varphi \mid \varphi_1 \wedge \varphi_2 \mid \langle\rho\rangle\varphi \\ \rho &::= \phi \mid \varphi? \mid \rho_1 + \rho_2 \mid \rho_1; \rho_2 \mid \rho^*\end{aligned}\tag{2.3}$$

where tt is a constant that stands for logical true and ϕ is a propositional formula over a set of symbols \mathcal{F} .

The syntax just defined is really similar to PDL [7], a well known and successful formalism in Computer Science for describing states and events of programs. However, LDL_f formulae are interpreted over finite traces instead of Labelled Transition Systems.

Before moving to the semantics, we can intuitively understand the meaning of the constructs. The second line of definition (2.3) is a Regular Temporal Specification RE_f , with the addition of the test operator $?$, typical of PDL. In $\langle\rho\rangle\varphi$, the RE_f expression ρ is used as a modal operator to move to future states: it states that there exists at least one

2.2 Reinforcement learning with restraining specifications

Restraining Bolt method [5][9].

Chapter 3

Learning to value fluents in games

The importance of correctly value the fluents.

3.1 Temporal constraints

How we can use temporal logic to express legal traces of interpretations; e.g. expected behaviours.

3.2 Assumptions

A temporal constraints aren't definitions; they are just minimal constraints. We need additional clues: visual description of fluents. Now follow my assumptions:

- Local properties (with regions I don't have to find elements in a frame).
- The property is visually apparent, inside the region.

Limitations and other ideas for a stronger grounding.

3.3 General structure of the model

Illustration and general description of the model.

3.4 Encoding

Encoder: the model, how it works, what does it learn, size of the encoding.

References: Training Restricted Boltzmann Machines and Deep Belief Networks [22][18].

3.4.1 Model: Deep Belief Network

3.4.2 What does it learn

3.5 Boolean functions

The fluents are true in a set of those configurations.

3.5.1 Learning with genetic algorithms

Ideas from concept learning; genetic algorithm.

References: Genetic Algorithms for Concept learning[14], Genetic Algorithms review[11].

3.5.2 Boolean rules

Representation of boolean functions and training details.

Chapter 4

AtariEyes package

Intro to the software. What we can do:

- Train a Reinforcement Learning agent.
- Train the features extraction.
- Run a Restraining Bolt while training and playing an agent.

4.1 How to use the software

4.1.1 Tools and setup

4.1.2 Commands

Small user reference.

4.2 Implementation

4.2.1 agent Module

training Module

playing Module

4.2.2 streaming Module

4.2.3 features Module

models Module

genetic Module

temporal Module

Chapter 5

Experiments

5.1 Breakout

5.1.1 Definitions

5.1.2 Training

5.1.3 Comments

5.2 Montezuma's Revenge

5.2.1 Definitions

5.2.2 Training

5.2.3 Comments

5.3 New example

I'll try to train one additional environment just to show a case in which the role of the temporal constraints is more evident, like in Breakout (something like a simple game with many rules).

Chapter 6

Conclusions and future work

What I have done (concretely); what I haven't done; how I'd improve the results and how to possibly relax some assumptions.

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