
CIS 471/571 (Fall 2020): Introduction to Artificial Intelligence

Assignment Project Exam Help

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Lecture 8: MDPs (Part 1)
WeChat: cstutorcs

Thanh H. Nguyen

Source: <http://ai.berkeley.edu/home.html>

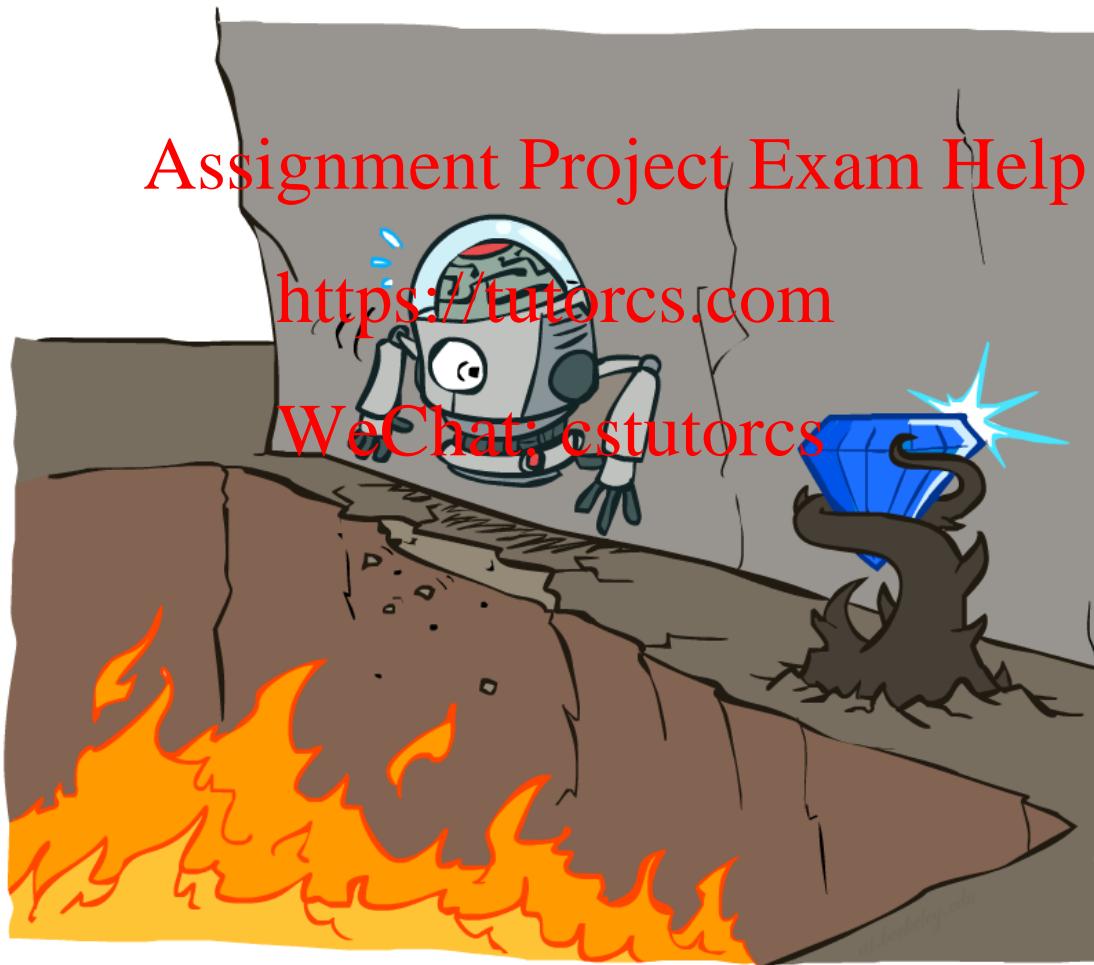
Reminder

- Project 2: Multi-agent Search
 - Deadline: Oct 27th, 2020

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- Homework 2: CSPs and Games
 - Deadline: Oct 24th, [WeChat: cstutorcs](https://tutorcs.com)

Non-Deterministic Search



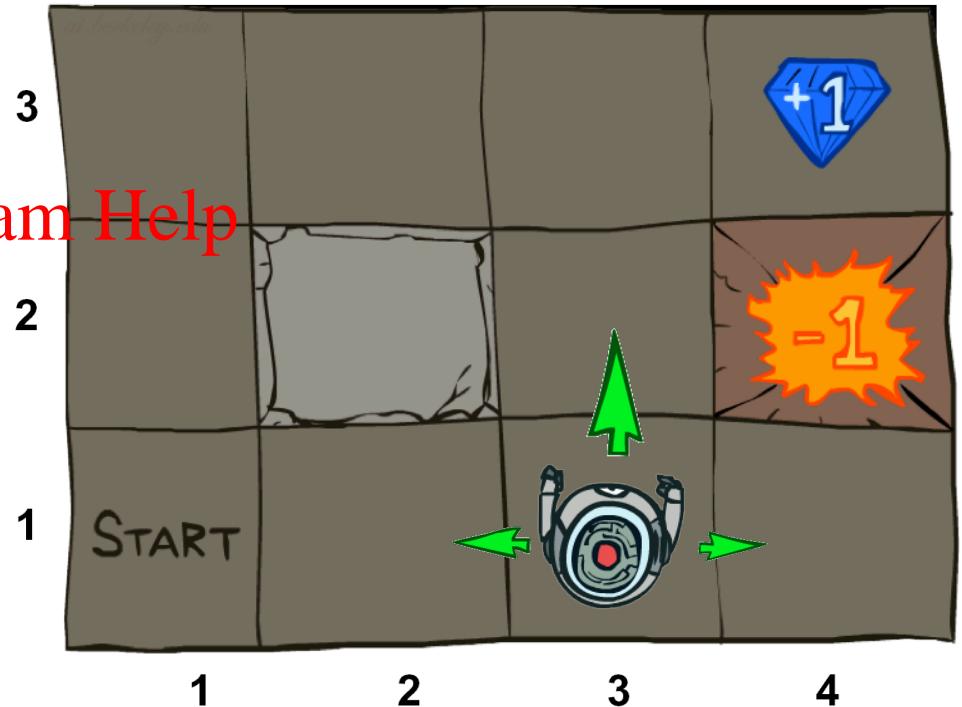
Example: Grid World

- A maze-like problem
 - The agent lives in a grid
 - Walls block the agent's path
- Noisy movement: actions do not always go as planned
 - 80% of the time, the action North takes the agent North
(if there is no wall there)
 - 10% of the time, North takes the agent West; 10% East
 - If there is a wall in the direction the agent would have been taken, the agent stays put
- The agent receives rewards each time step
 - Small “living” reward each step (can be negative)
 - Big rewards come at the end (good or bad)
- Goal: maximize sum of rewards

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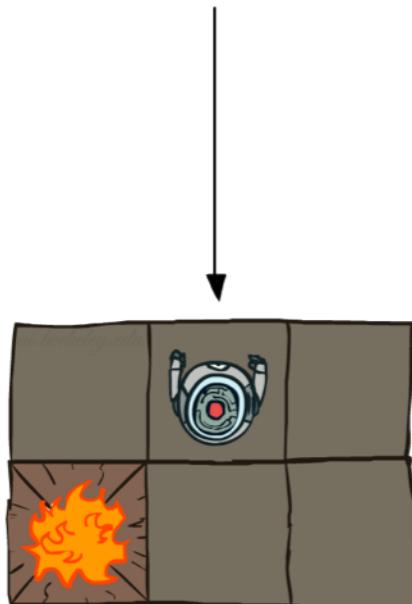
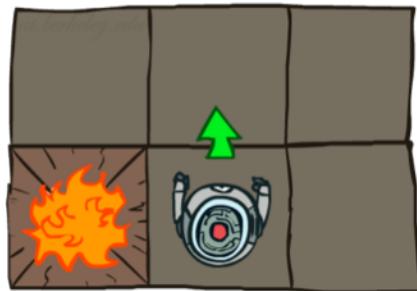
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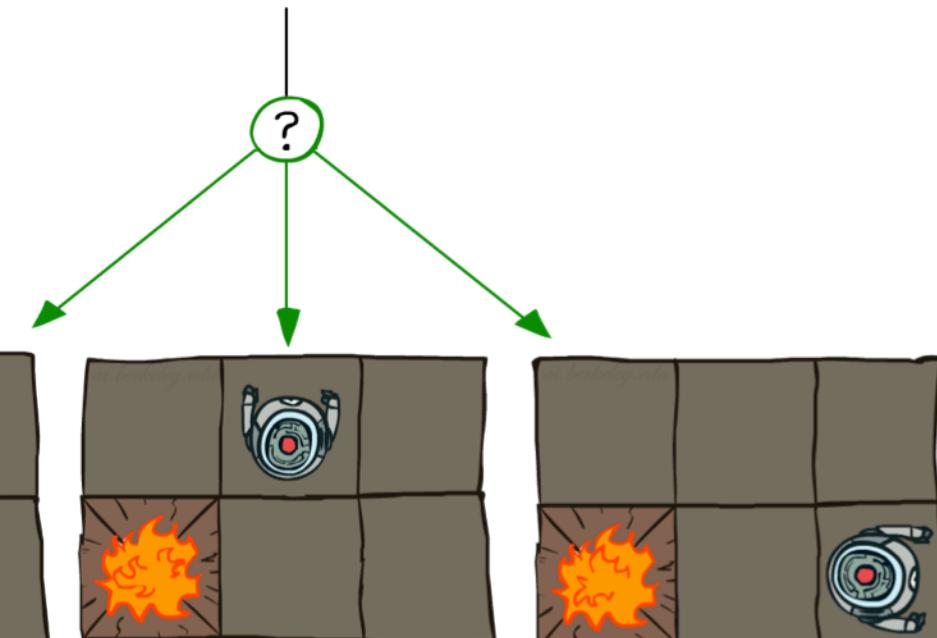


Grid World Actions

Deterministic Grid World



Stochastic Grid World



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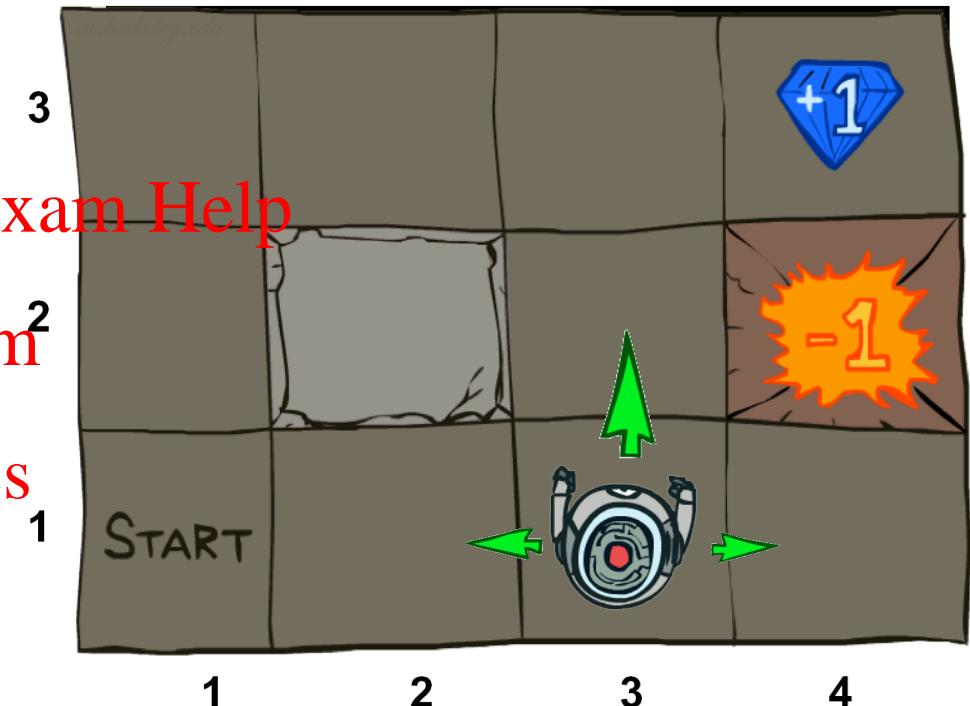
Markov Decision Processes

- An MDP is defined by:
 - A set of states $s \in S$
 - A set of actions $a \in A$
 - A transition function $T(s, a, s')$
 - Probability that a from s leads to s' , i.e., $P(s' | s, a)$
 - Also called the model or the dynamics
- A reward function $R(s, a, s')$
 - Sometimes just $R(s)$ or $R(s')$
- A start state
- Maybe a terminal state

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- MDPs are non-deterministic search problems
 - One way to solve them is with expectimax search
 - We'll have a new tool soon



What is Markov about MDPs?

- “Markov” generally means that given the present state, the future and the past are independent
- For Markov decision processes, “Markov” means action outcomes depend only on the current state
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$$P(S_{t+1} = s' | S_t = s_t, A_t = a_t, S_{t-1} = s_{t-1}, A_{t-1}, \dots, S_0 = s_0)$$

=

$$P(S_{t+1} = s' | S_t = s_t, A_t = a_t)$$



Andrey Markov
(1856-1922)

- This is just like search, where the successor function could only depend on the current state (not the history)



Policies

- In deterministic single-agent search problems, we wanted an optimal **plan**, or sequence of actions, from start to a goal

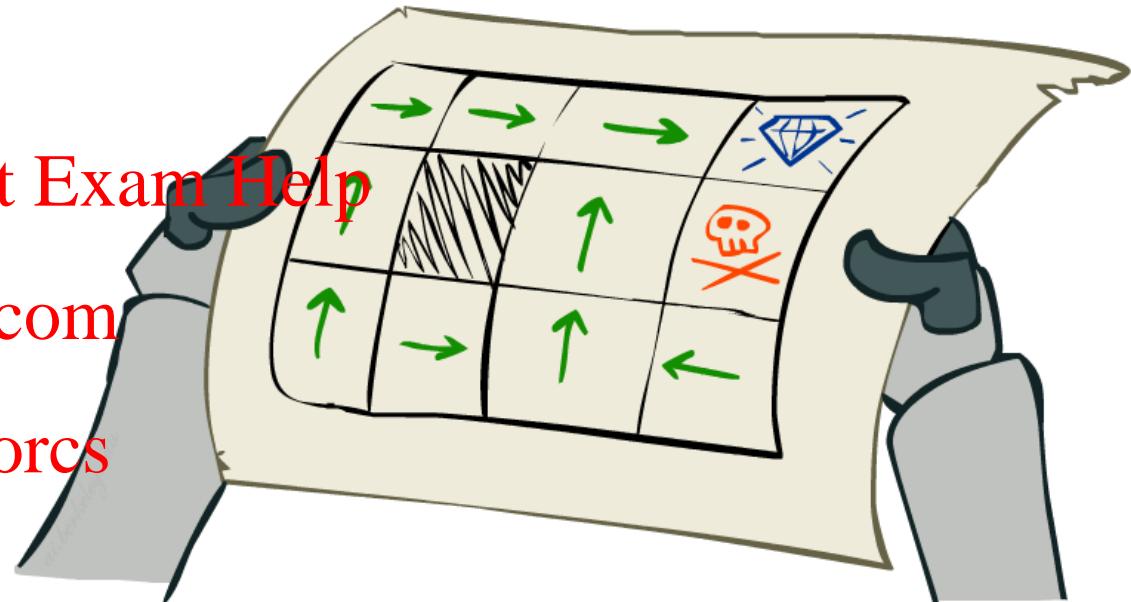
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- For MDPs, we want an optimal policy π^* :
 $S \rightarrow A$

- A policy π gives an action for each state
- An optimal policy is one that maximizes expected utility if followed
- An explicit policy defines a reflex agent

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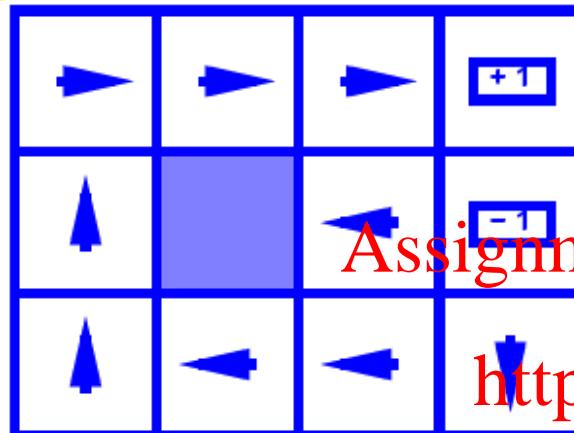
- Expectimax didn't compute entire policies
 - It computed the action for a single state only



Optimal policy when $R(s, a, s') = -0.03$ for all non-terminals s

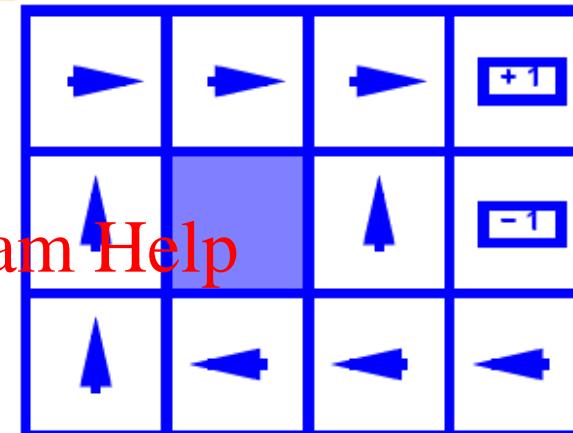


Optimal Policies

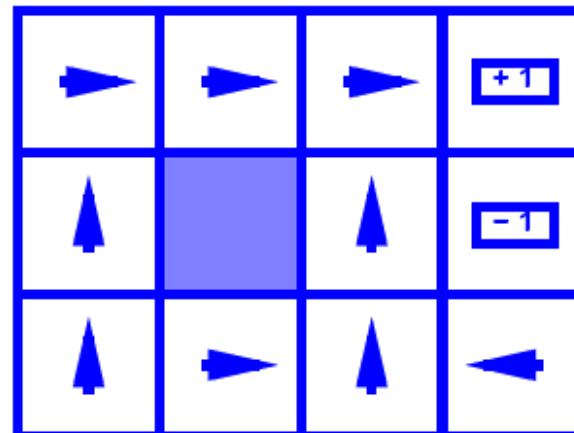


$R(s) = -0.01$

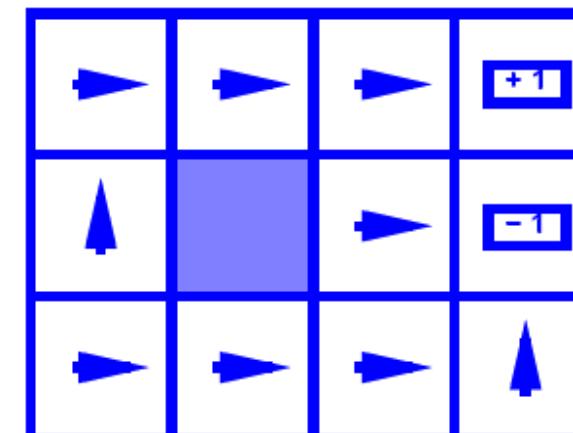
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$R(s) = -0.03$



$R(s) = -0.4$



$R(s) = -2.0$

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Example: Racing

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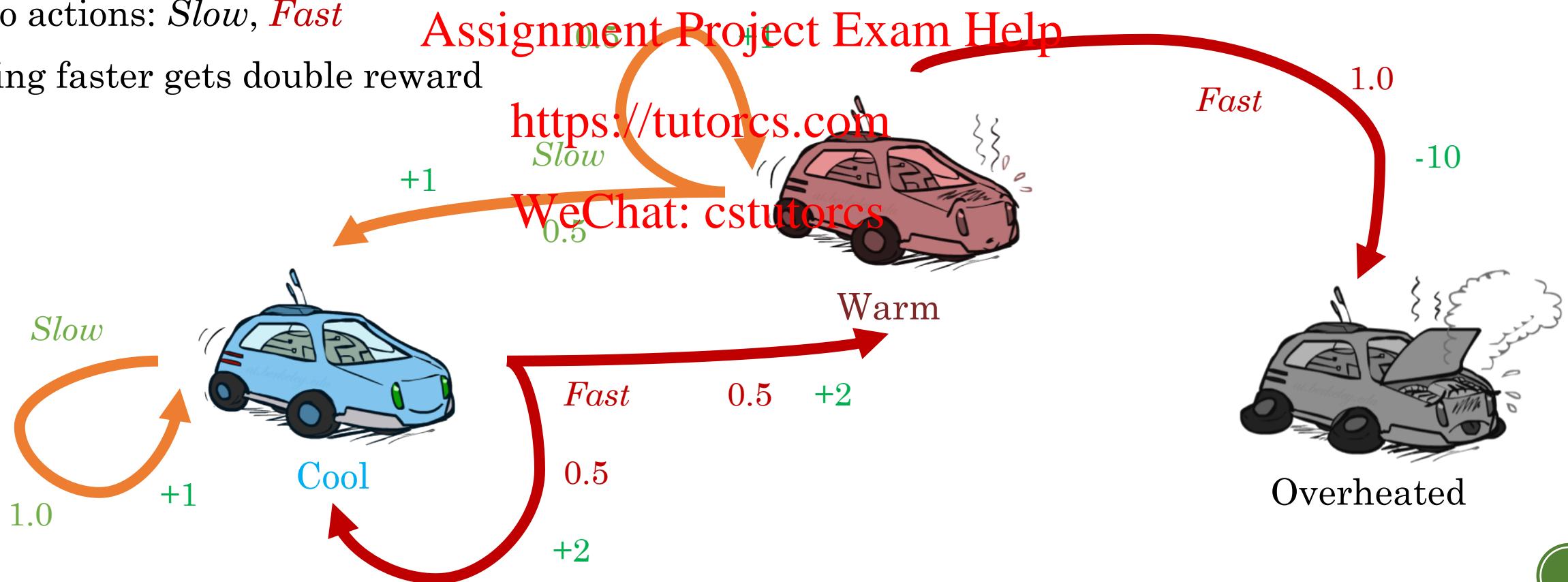
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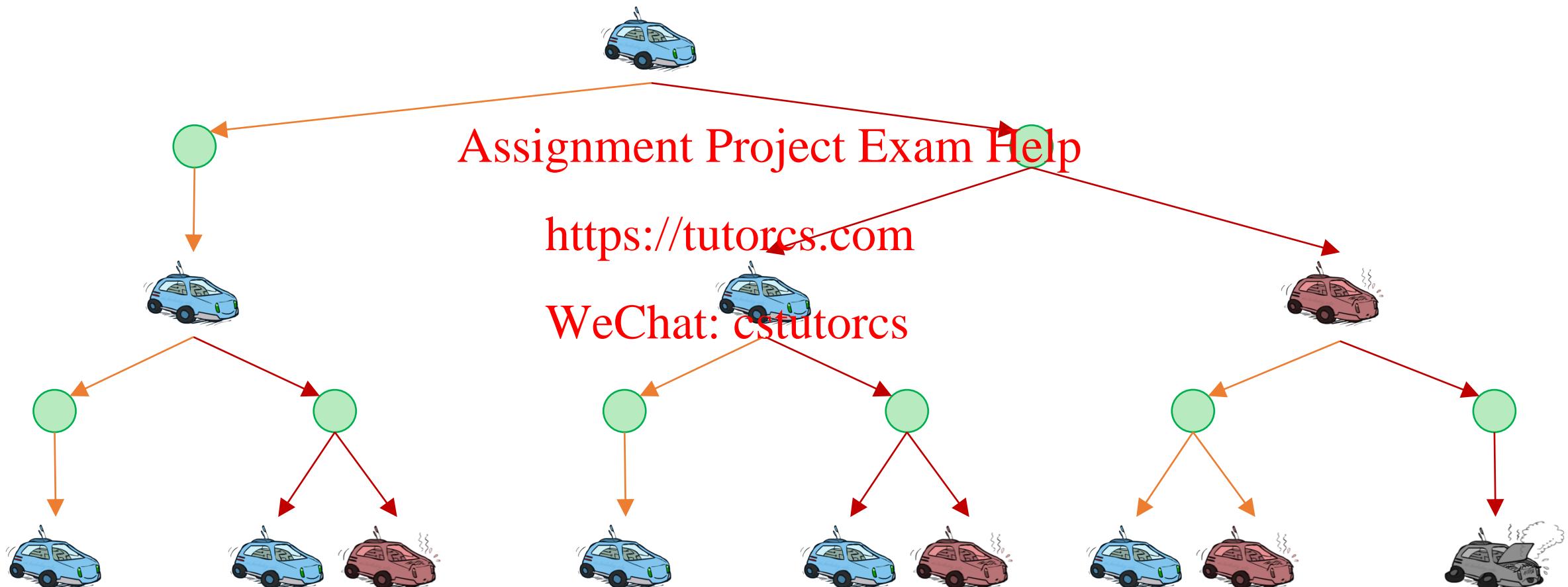


Example: Racing

- A robot car wants to travel far, quickly
- Three states: Cool, Warm, Overheated
- Two actions: *Slow*, *Fast*
- Going faster gets double reward

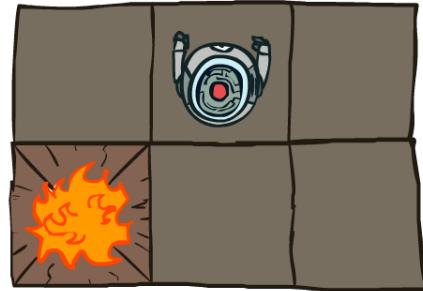
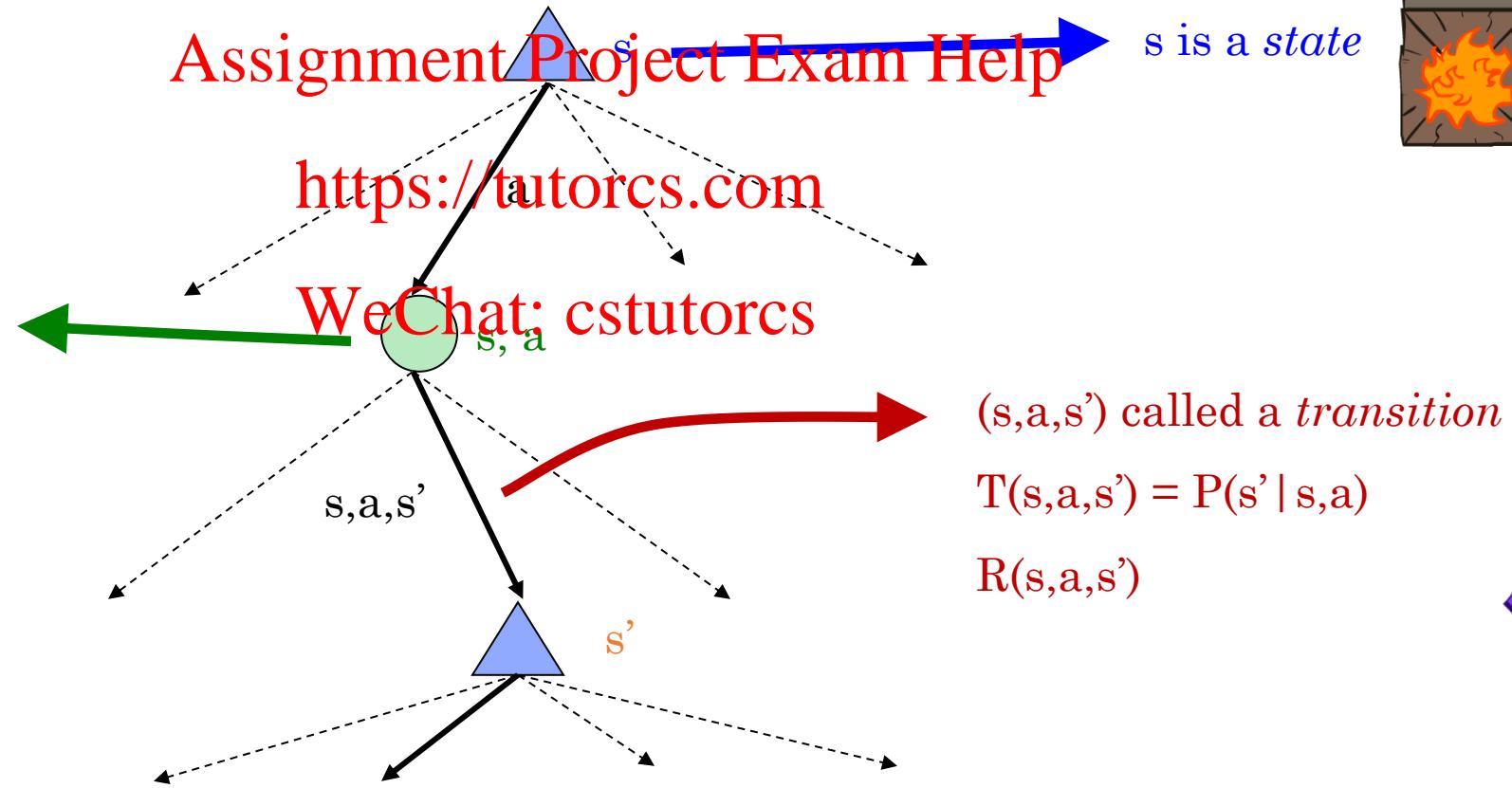


Racing Search Tree

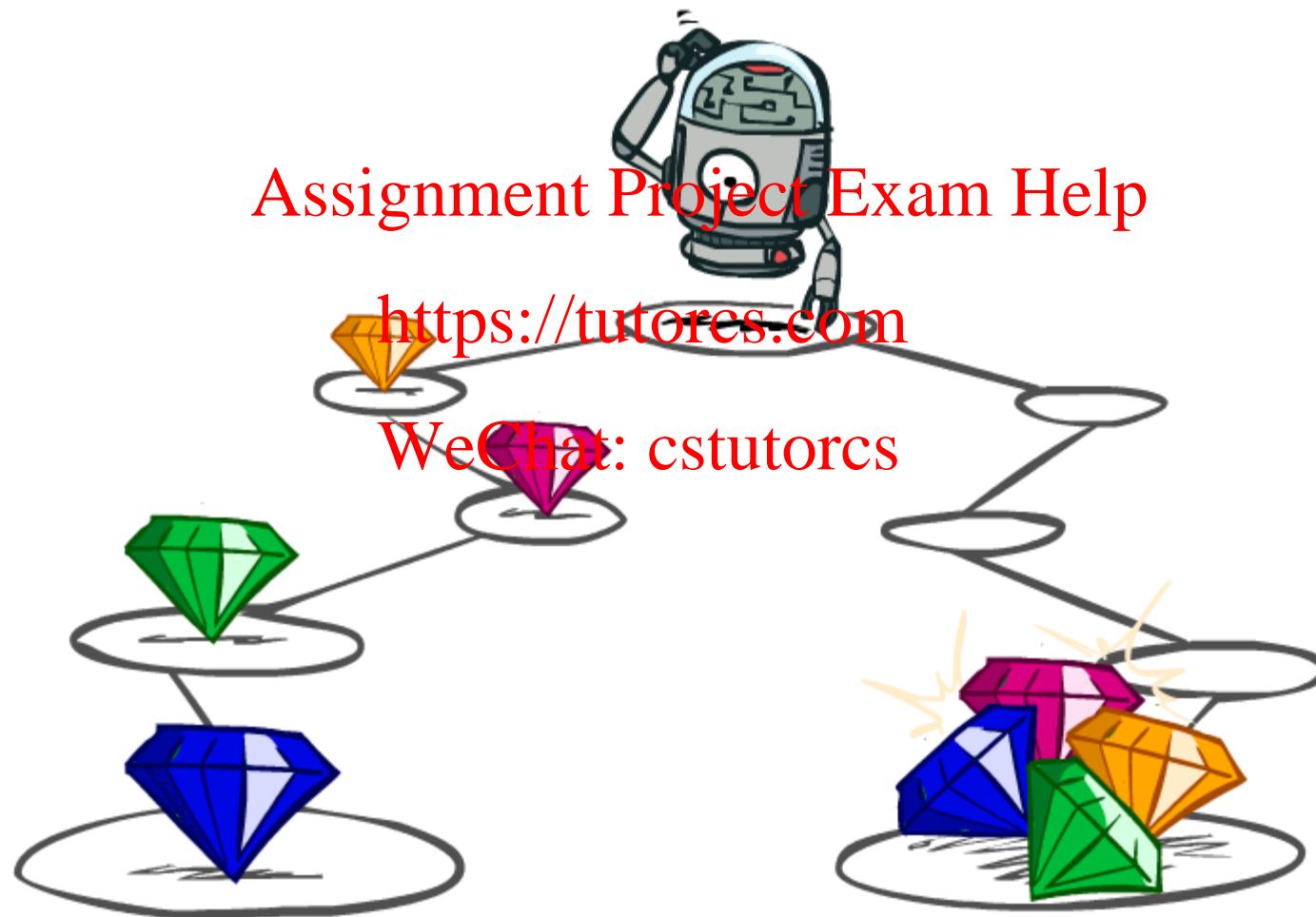


MDP Search Trees

- Each MDP state projects an expectimax-like search tree

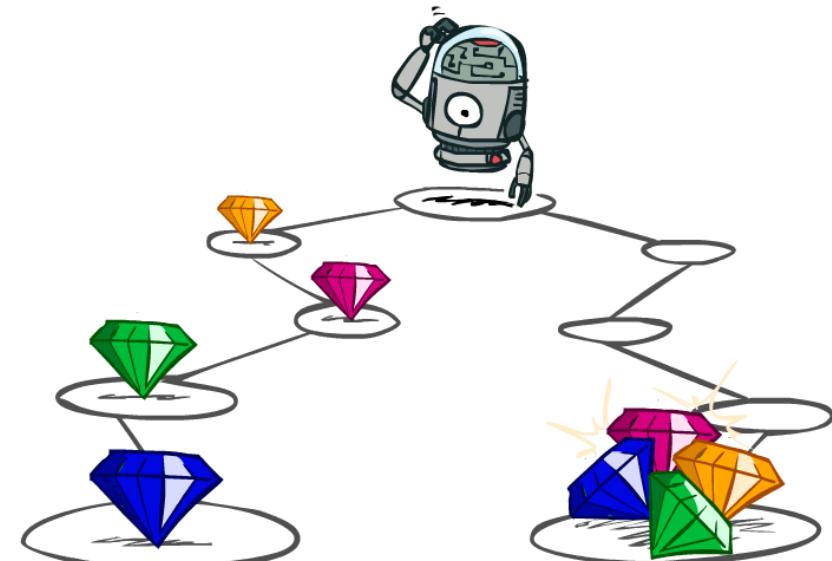


Utilities of Sequences



Utilities of Sequences

- What preferences should an agent have over reward sequences?
- More or less? [1, 2, 2] or [2, 3, 4]
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https://tutorcs.com](https://tutorcs.com)
- Now or later? [0, 0, 1] WeChat:[1, 0, 0]



Discounting

- It's reasonable to maximize the sum of rewards
- It's also reasonable to prefer rewards now to rewards later
- One solution: values of rewards decay exponentially

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1

Worth Now

γ

Worth Next Step

γ^2

Worth In Two Steps



Discounting

- How to discount?

- Each time we descend a level, we multiply in the discount once

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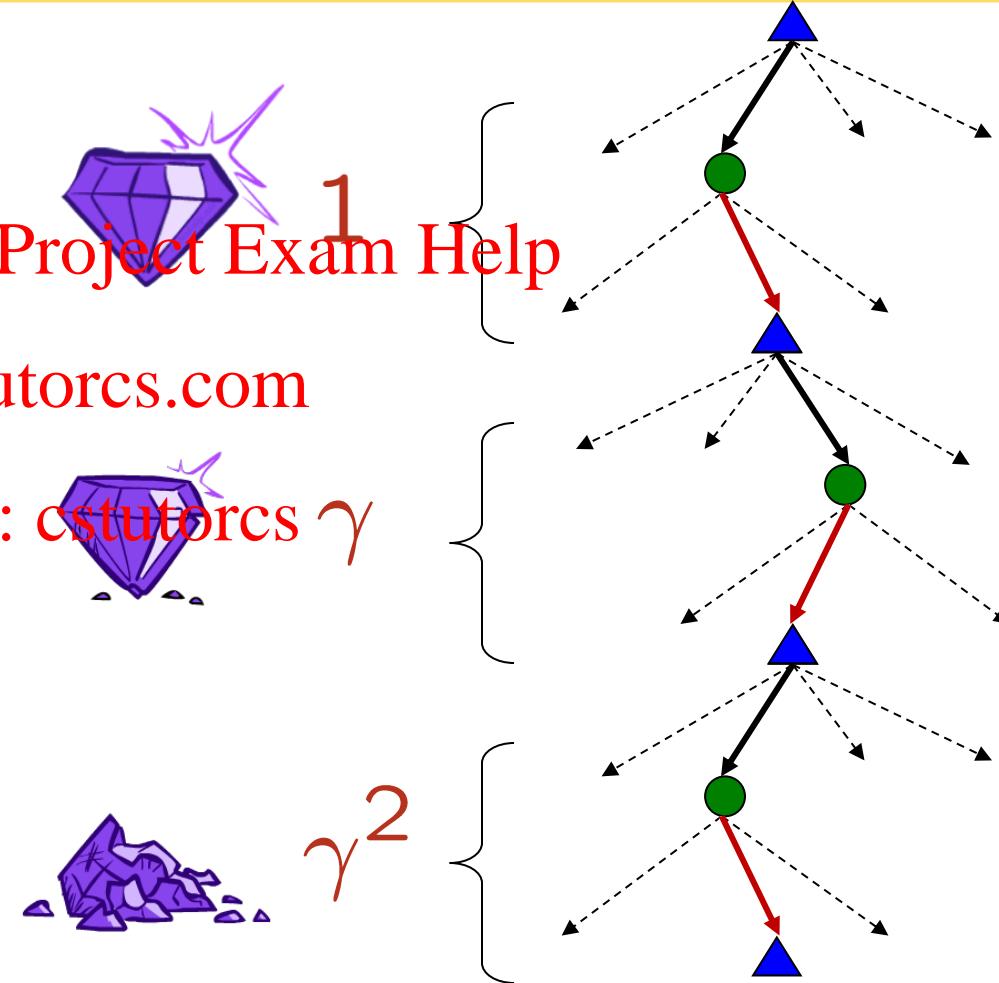
WeChat: cstutorcs γ

- Why discount?

- Sooner rewards probably do have higher utility than later rewards
 - Also helps our algorithms converge

- Example: discount of 0.5

- $U([1,2,3]) = 1*1 + 0.5*2 + 0.25*3$
 - $U([1,2,3]) < U([3,2,1])$



Stationary Preferences

- Theorem: if we assume stationary preferences:

$$[a_1, a_2, \dots] \succ [b_1, b_2, \dots]$$

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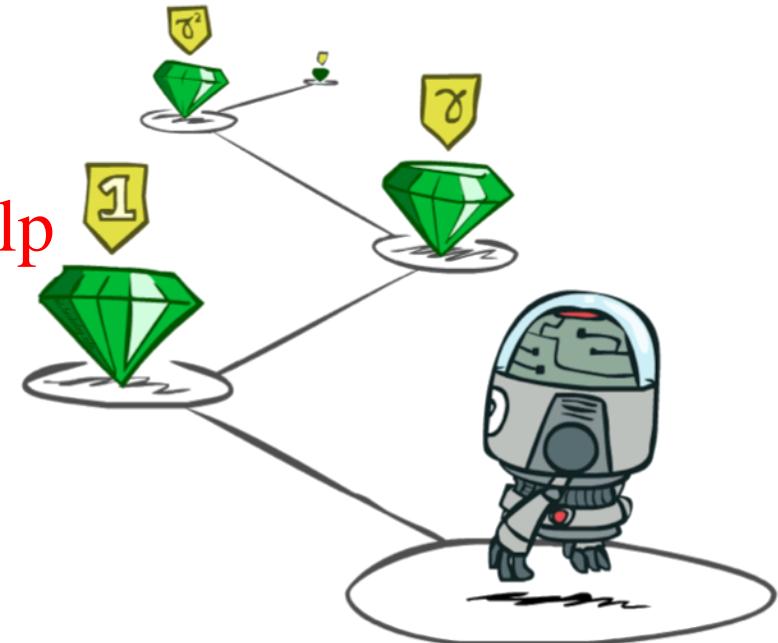
$$[r, a_1, a_2, \dots] \succ [r, b_1, b_2, \dots]$$

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- Then: there are only two ways to define utilities

- Additive utility: $U([r_0, r_1, r_2, \dots]) = r_0 + r_1 + r_2 + \dots$

- Discounted utility: $U([r_0, r_1, r_2, \dots]) = r_0 + \gamma r_1 + \gamma^2 r_2 \dots$



Quiz: Discounting

- Given:

10				1
a	b	c	d	e

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- Actions: East, West, and Exit (only available in exit states a, e)
- Transitions: deterministic

- Quiz 1: For $\gamma = 1$, what is the optimal policy?

10				1
----	--	--	--	---

- Quiz 2: For $\gamma = 0.1$, what is the optimal policy?

10				1
----	--	--	--	---

- Quiz 3: For which γ are West and East equally good when in state d?



Infinite Utilities?!

- Problem: What if the game lasts forever? Do we get infinite rewards?

- Solutions:

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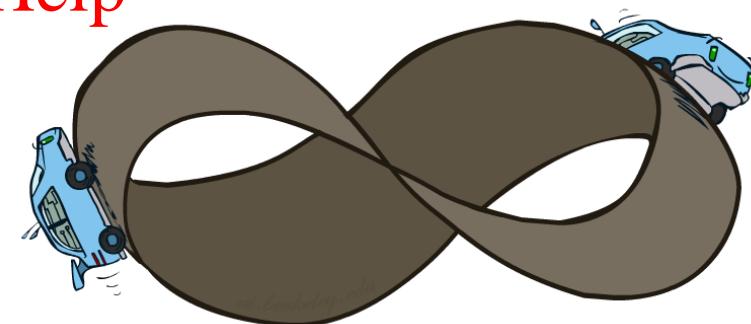
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- Finite horizon: (similar to depth-limited search)
 - Terminate episodes after a fixed T steps (e.g. life)
 - Gives nonstationary policies (π depends on time left)
- Discounting: use $0 < \gamma < 1$

$$U([r_0, \dots r_\infty]) = \sum_{t=0}^{\infty} \gamma^t r_t \leq R_{\max}/(1 - \gamma)$$

- Smaller γ means smaller “horizon” – shorter term focus
- Absorbing state: guarantee that for every policy, a terminal state will eventually be reached (like “overheated” for racing)



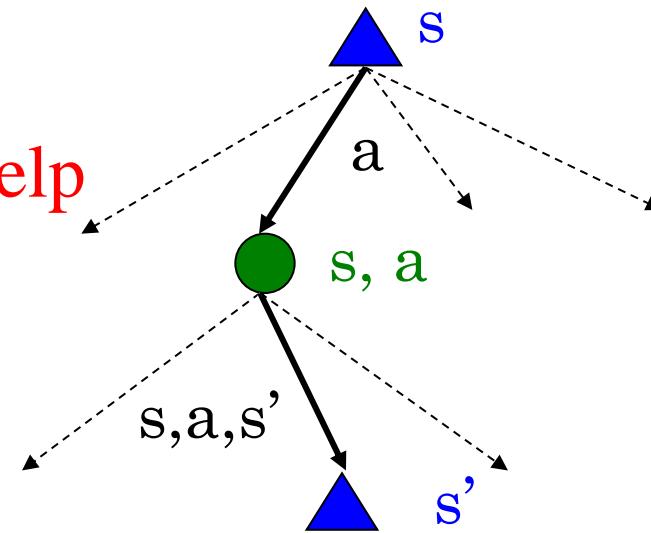
Recap: Defining MDPs

- Markov decision processes:

- Set of states S
- Start state s_0
- Set of actions A
- Transitions $P(s' | s, a)$ (or $T(s, a, s')$)
- Rewards $R(s, a, s')$ (and discount γ)

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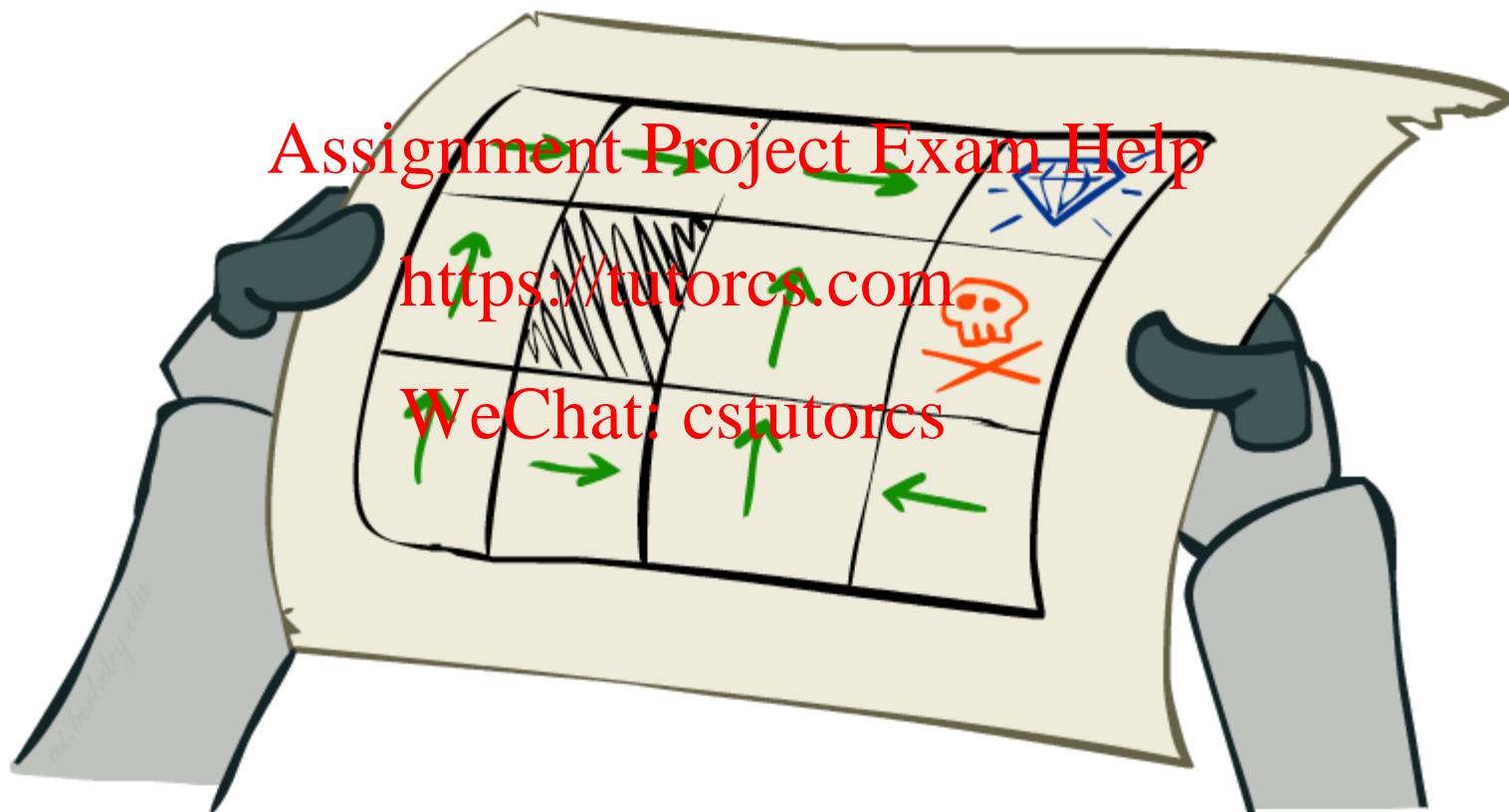


- MDP quantities so far:

- Policy = Choice of action for each state
- Utility = sum of (discounted) rewards



Solving MDPs



Optimal Quantities

- The value (utility) of a state s :

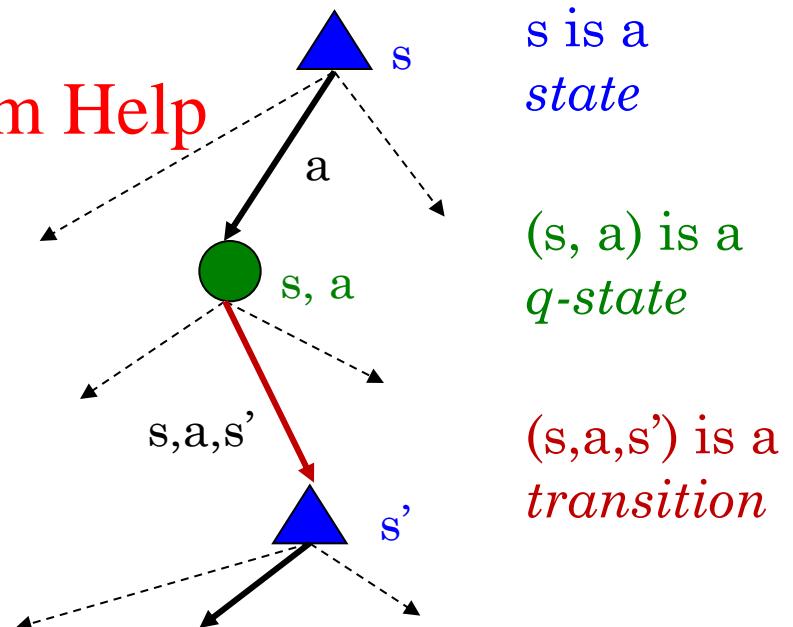
$V^*(s)$ = expected utility starting in s and acting optimally

- The value (utility) of a q-state (s,a) :

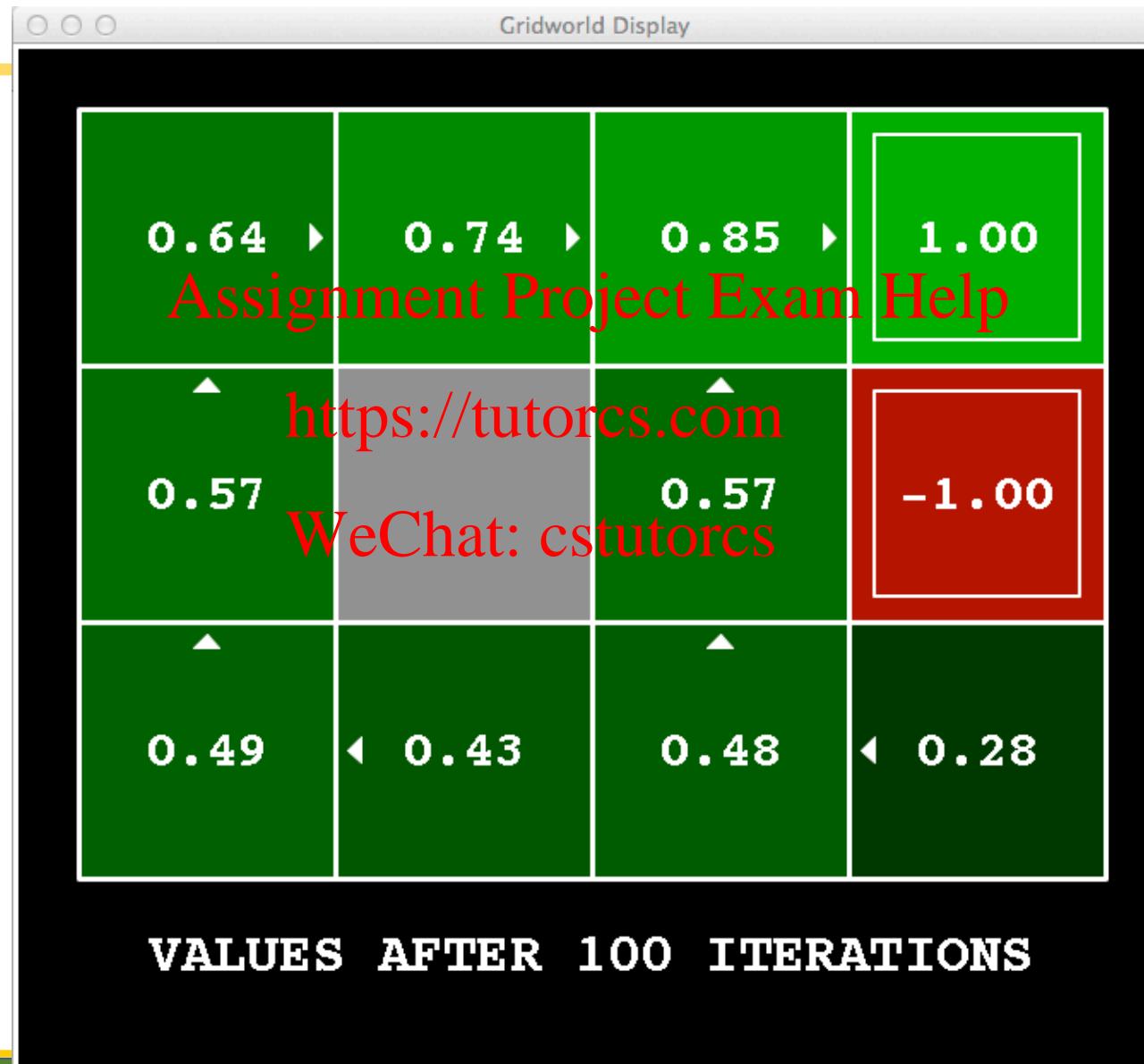
$Q^*(s,a)$ = expected utility starting out having taken action a from state s and (thereafter) acting optimally

- The optimal policy:

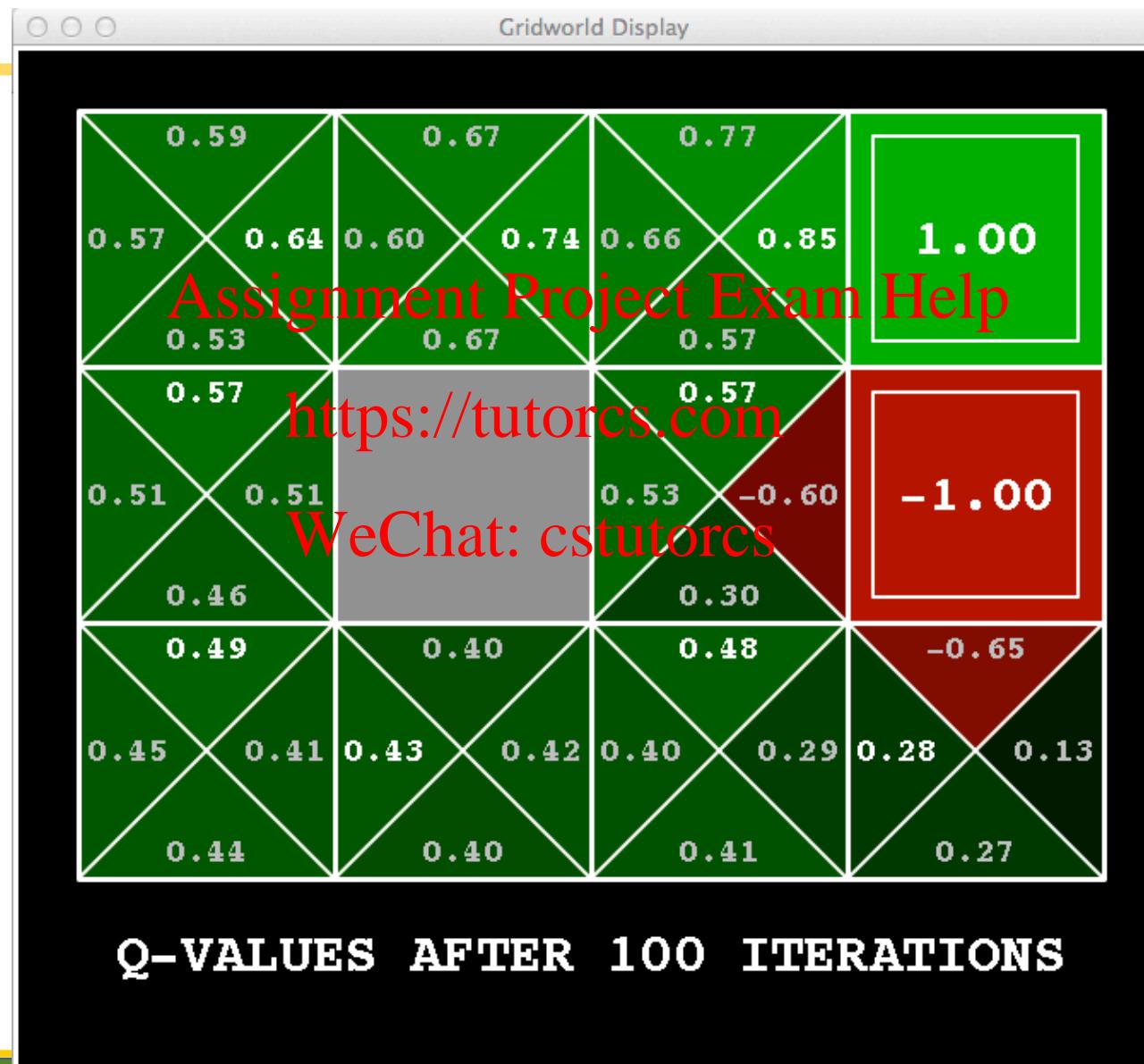
$\pi^*(s)$ = optimal action from state s



Snapshot of Demo – Gridworld V Values



Snapshot of Demo – Gridworld Q Values



Noise = 0.2
Discount = 0.9
Living reward = 0



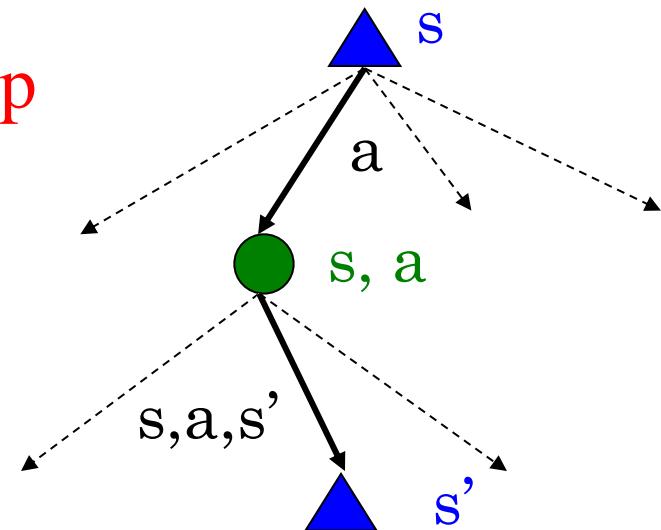
Values of States

- Fundamental operation: compute the (expectimax) value of a state
 - Expected utility under optimal action
 - Average sum of (discounted) rewards
 - This is just what expectimax computed!
<https://tutorcs.com>
- Recursive definition of Value: cstutorcs

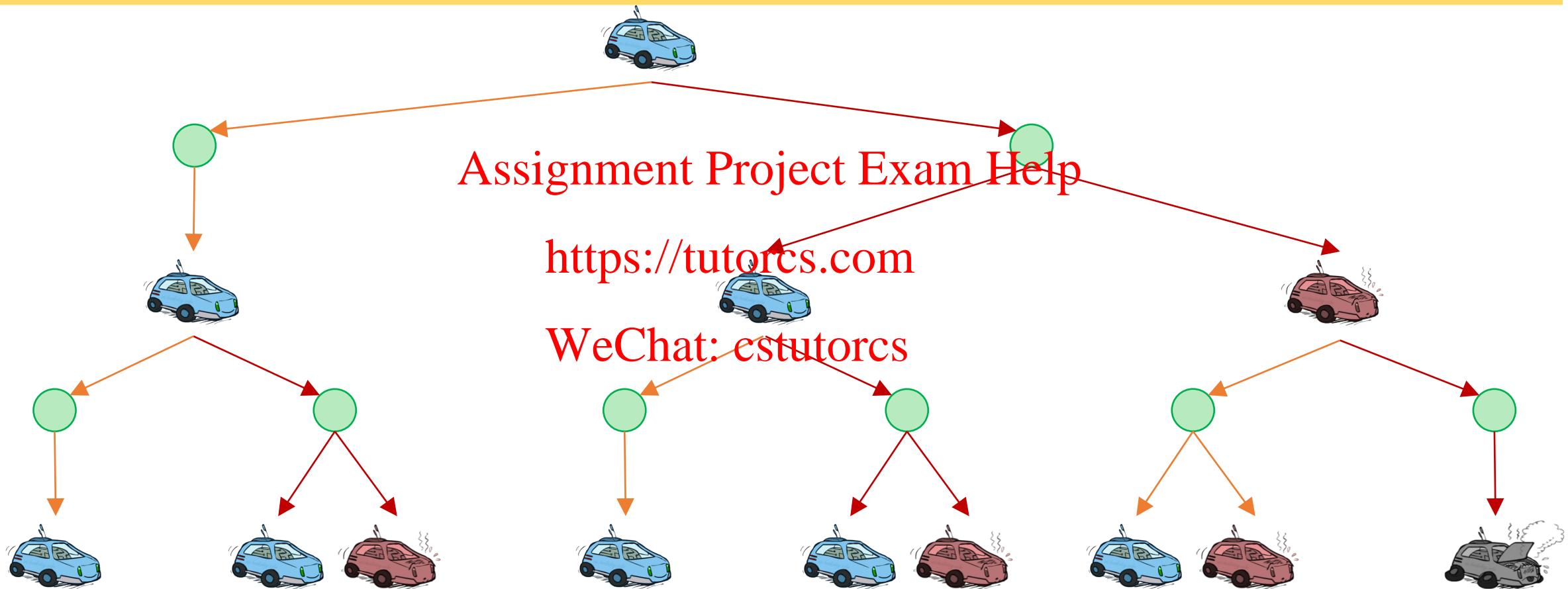
$$V^*(s) = \max_a Q^*(s, a)$$

$$Q^*(s, a) = \sum_{s'} T(s, a, s') [R(s, a, s') + \gamma V^*(s')]$$

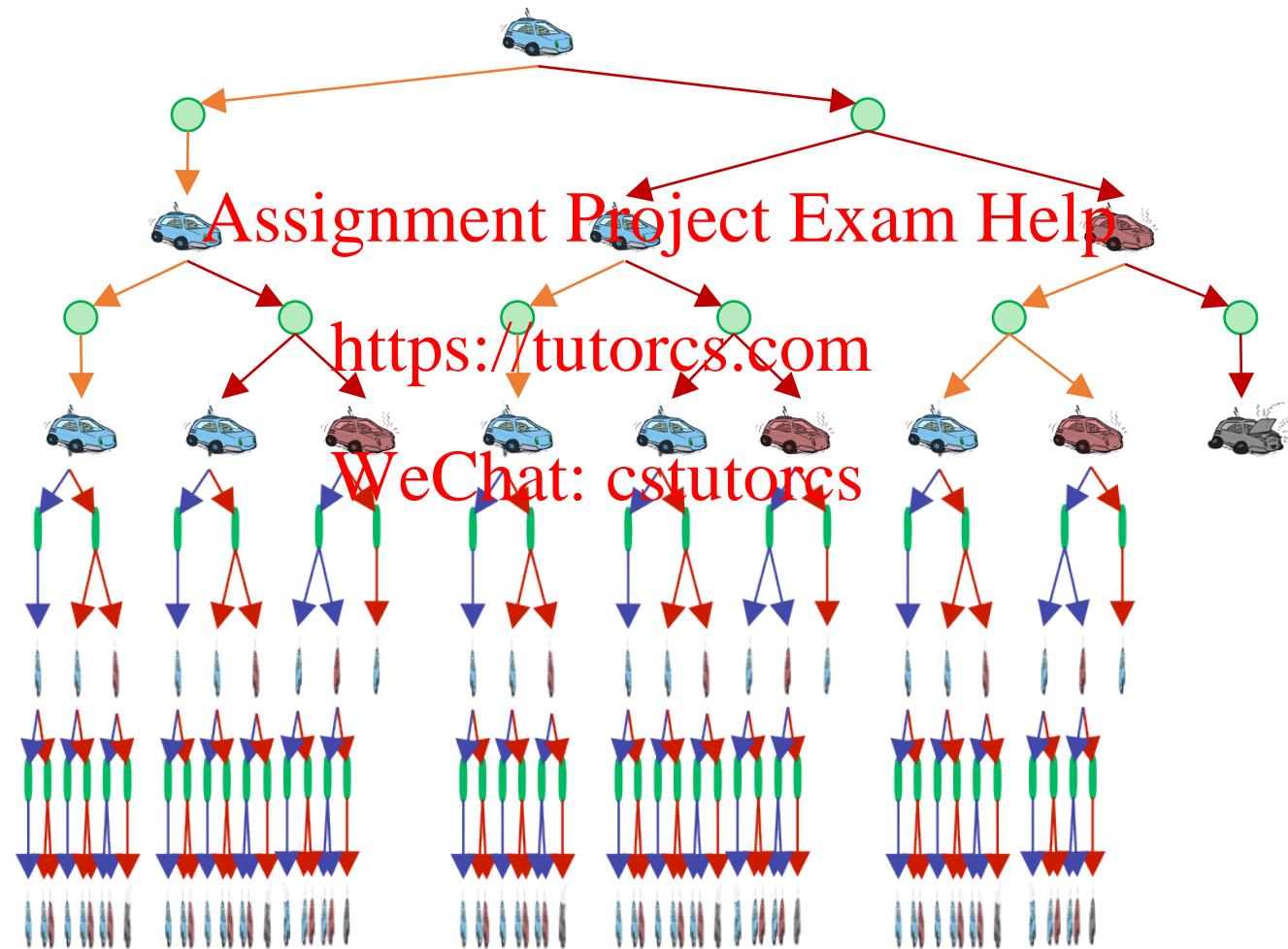
$$V^*(s) = \max_a \sum_{s'} T(s, a, s') [R(s, a, s') + \gamma V^*(s')]$$



Racing Search Tree

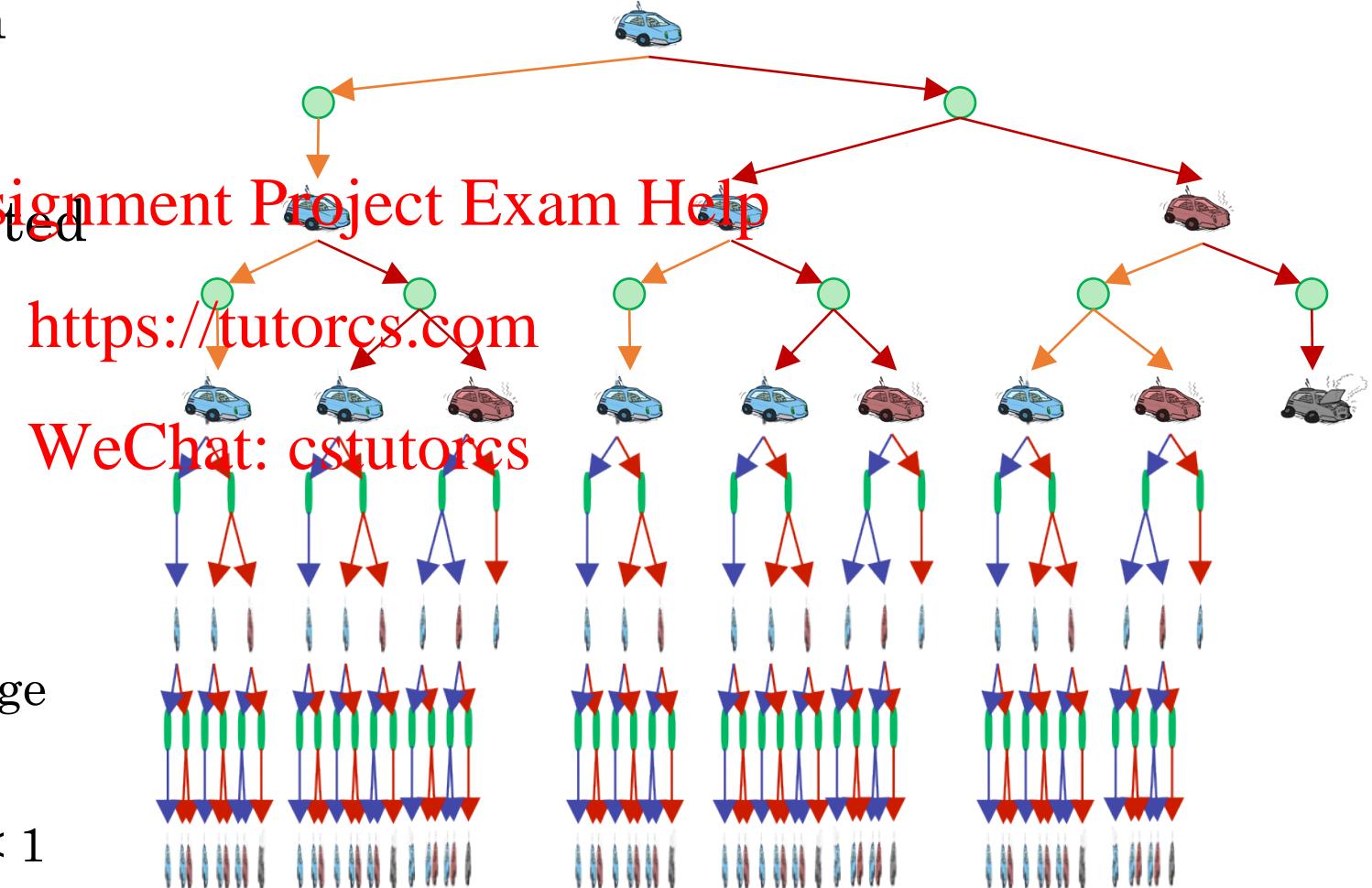


Racing Search Tree



Racing Search Tree

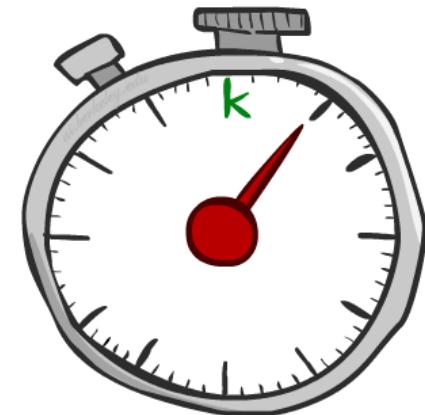
- We're doing way too much work with expectimax!
- Problem: States are repeated
 - Idea: Only compute needed quantities once
- Problem: Tree goes on forever
 - Idea: Do a depth-limited computation, but with increasing depths until change is small
 - Note: deep parts of the tree eventually don't matter if $\gamma < 1$



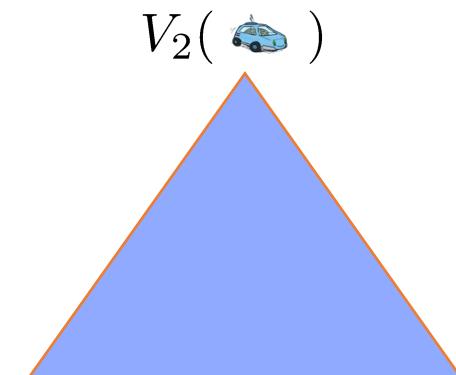
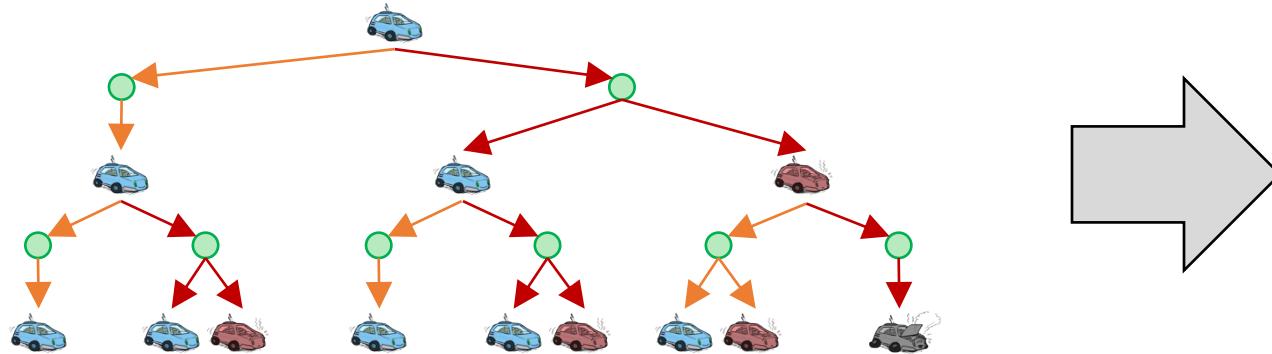
Time-Limited Values

- Key idea: time-limited values
- Define $V_k(s)$ to be the optimal value of s if the game ends in k more time steps
 - Equivalently, it's what a depth- k expectimax would give from s

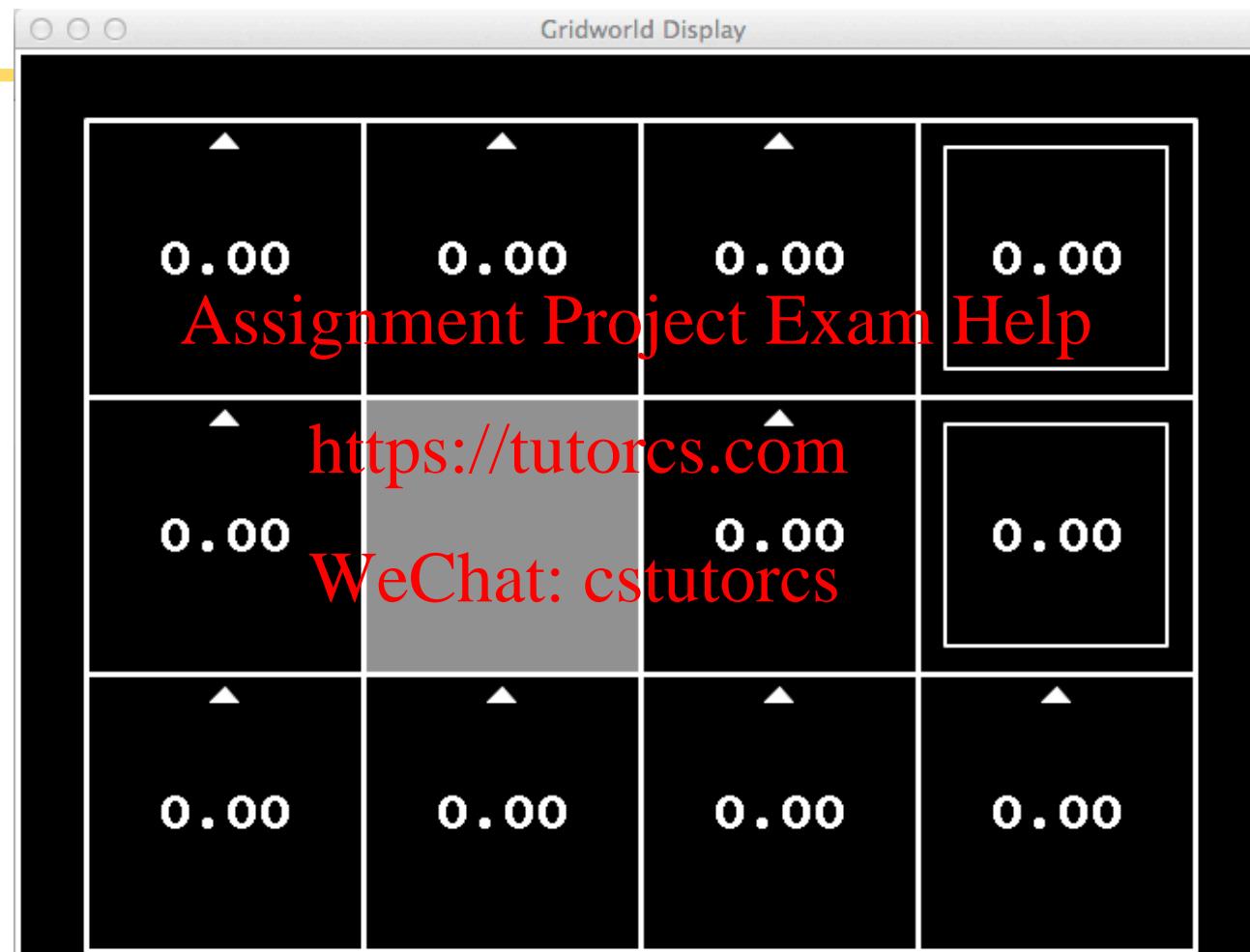
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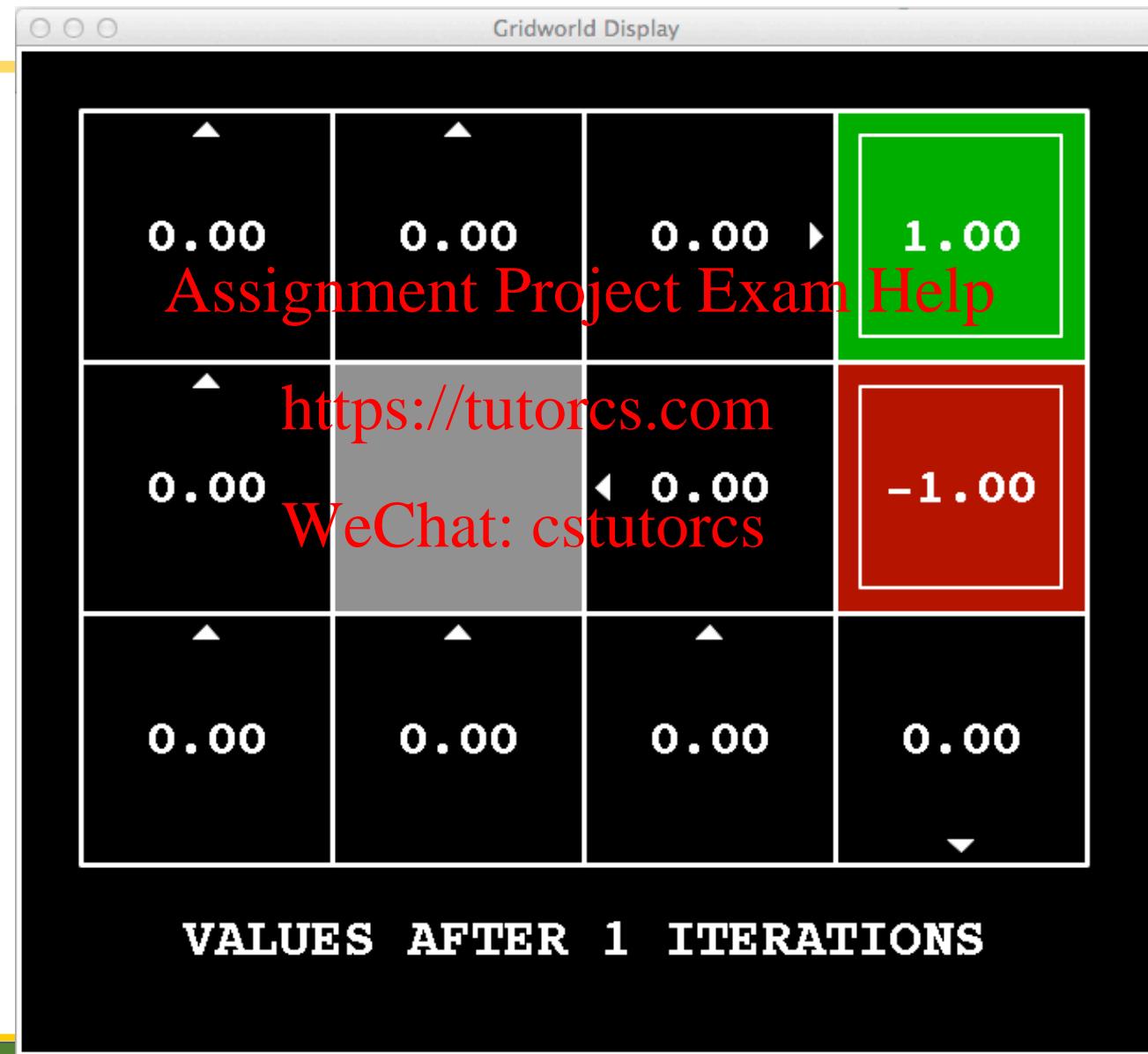
$k=0$



Noise = 0.2
Discount = 0.9
Living reward = 0



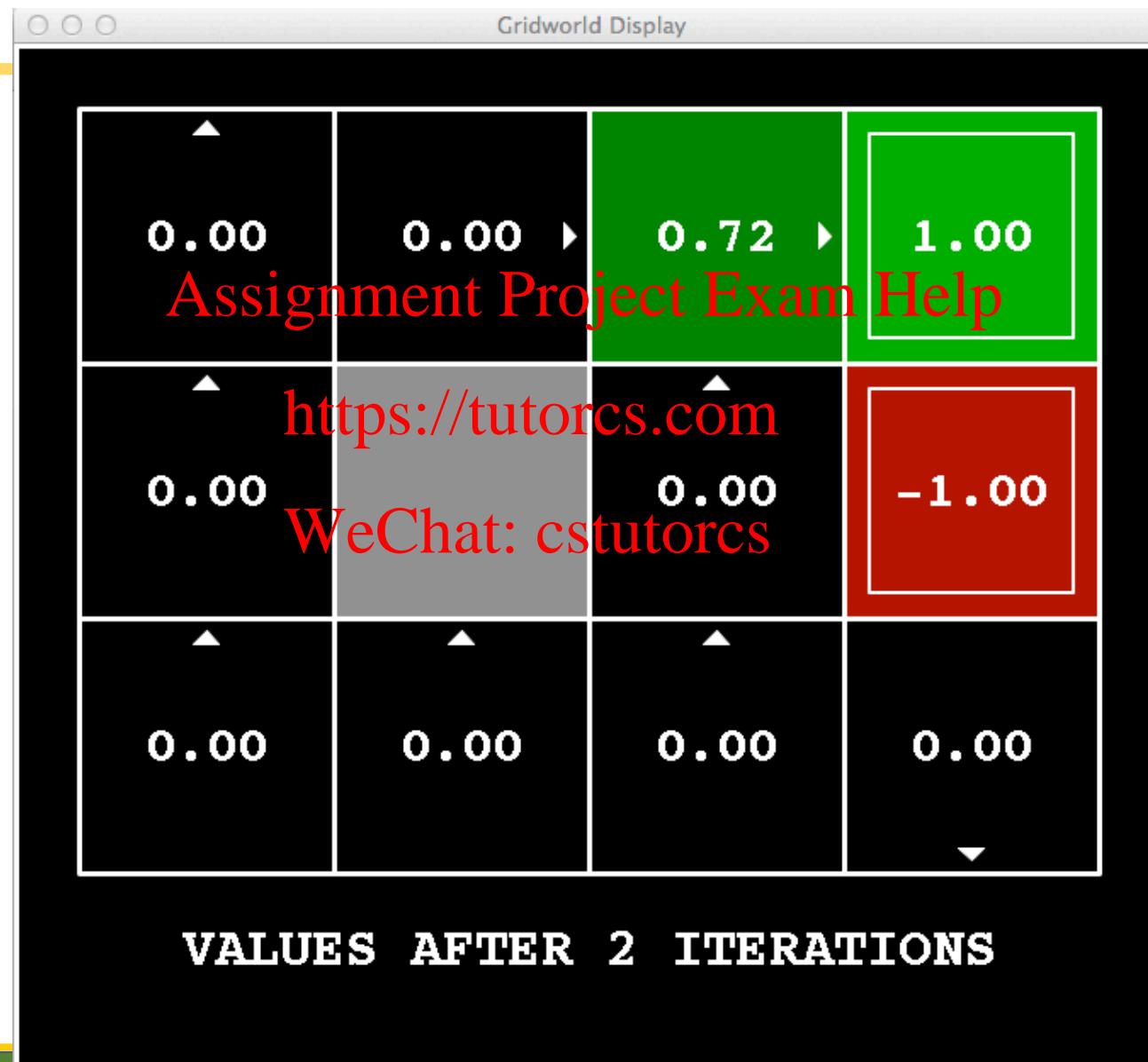
$k=1$



Noise = 0.2
Discount = 0.9
Living reward = 0



$k=2$



Noise = 0.2
Discount = 0.9
Living reward = 0



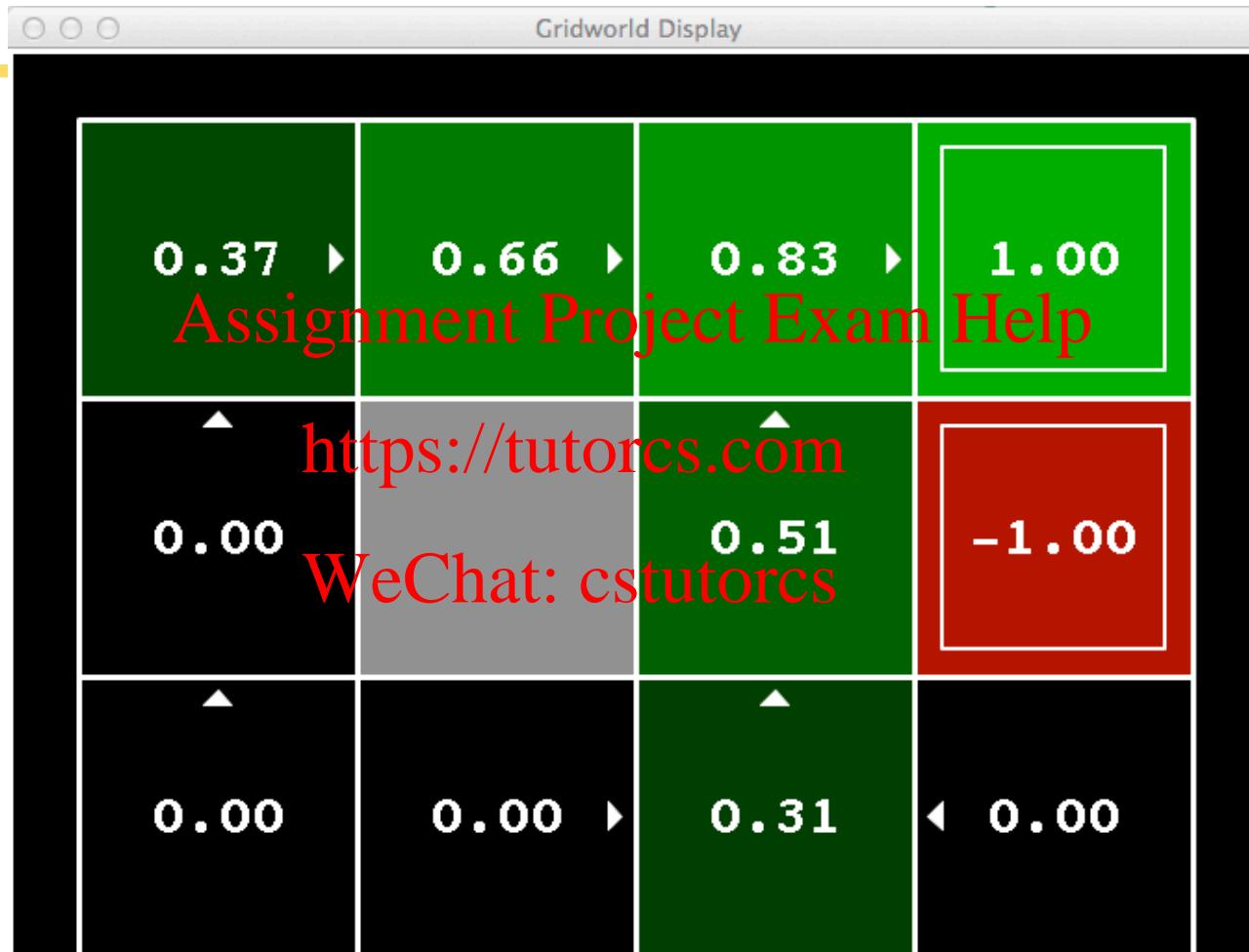
$k=3$



Noise = 0.2
Discount = 0.9
Living reward = 0



$k=4$

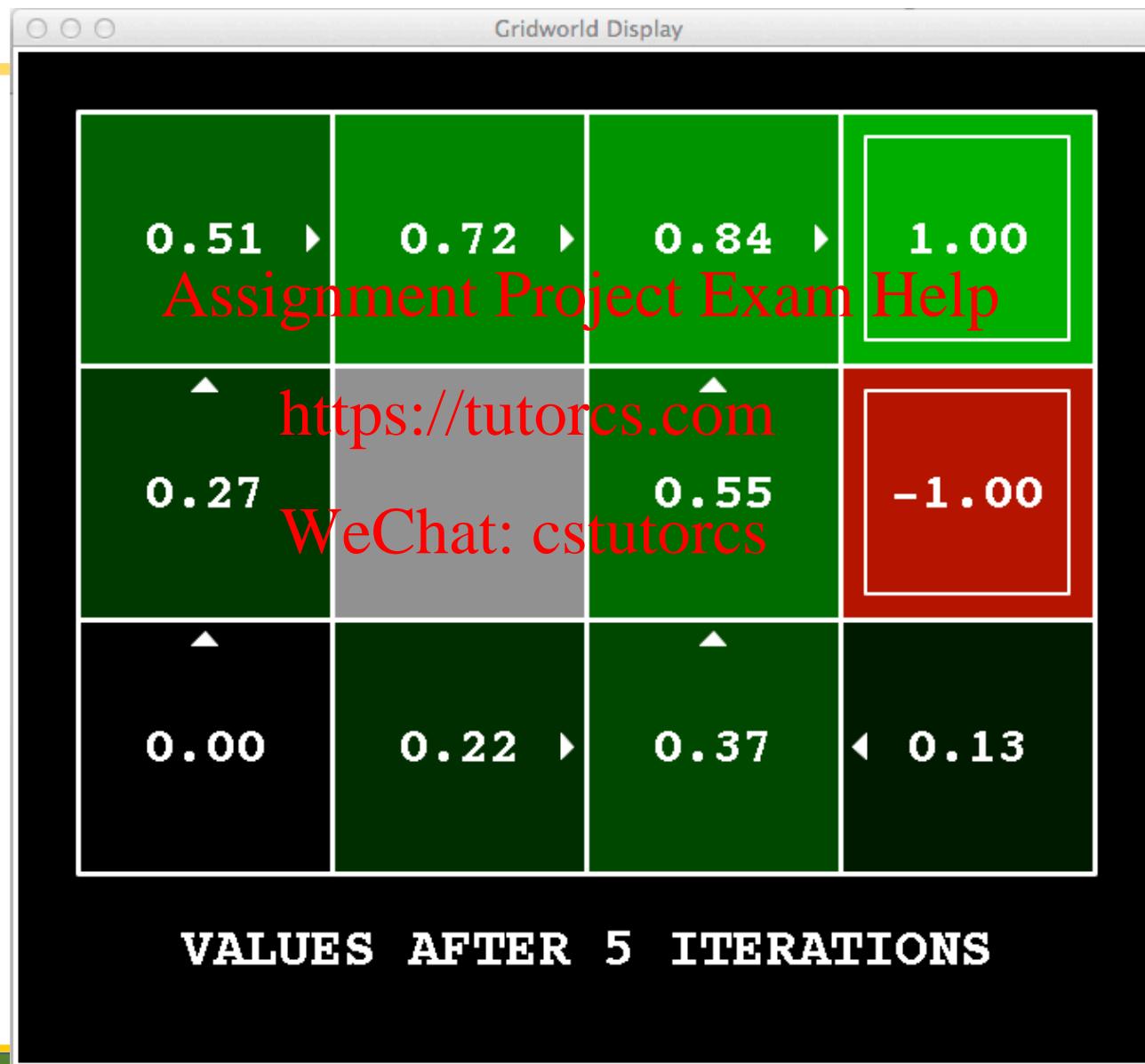


VALUES AFTER 4 ITERATIONS

Noise = 0.2
Discount = 0.9
Living reward = 0



$k=5$



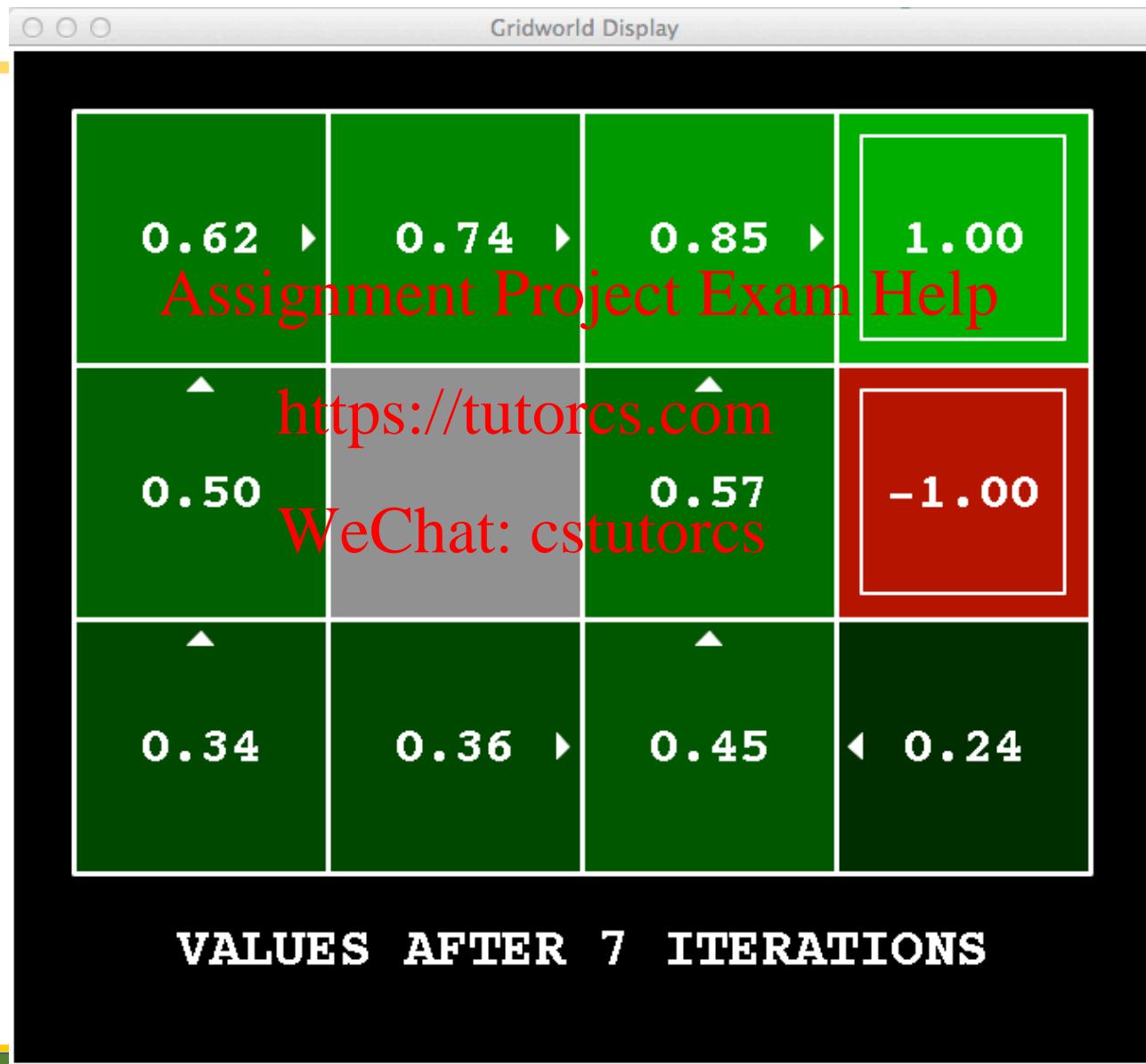
Noise = 0.2
Discount = 0.9
Living reward = 0



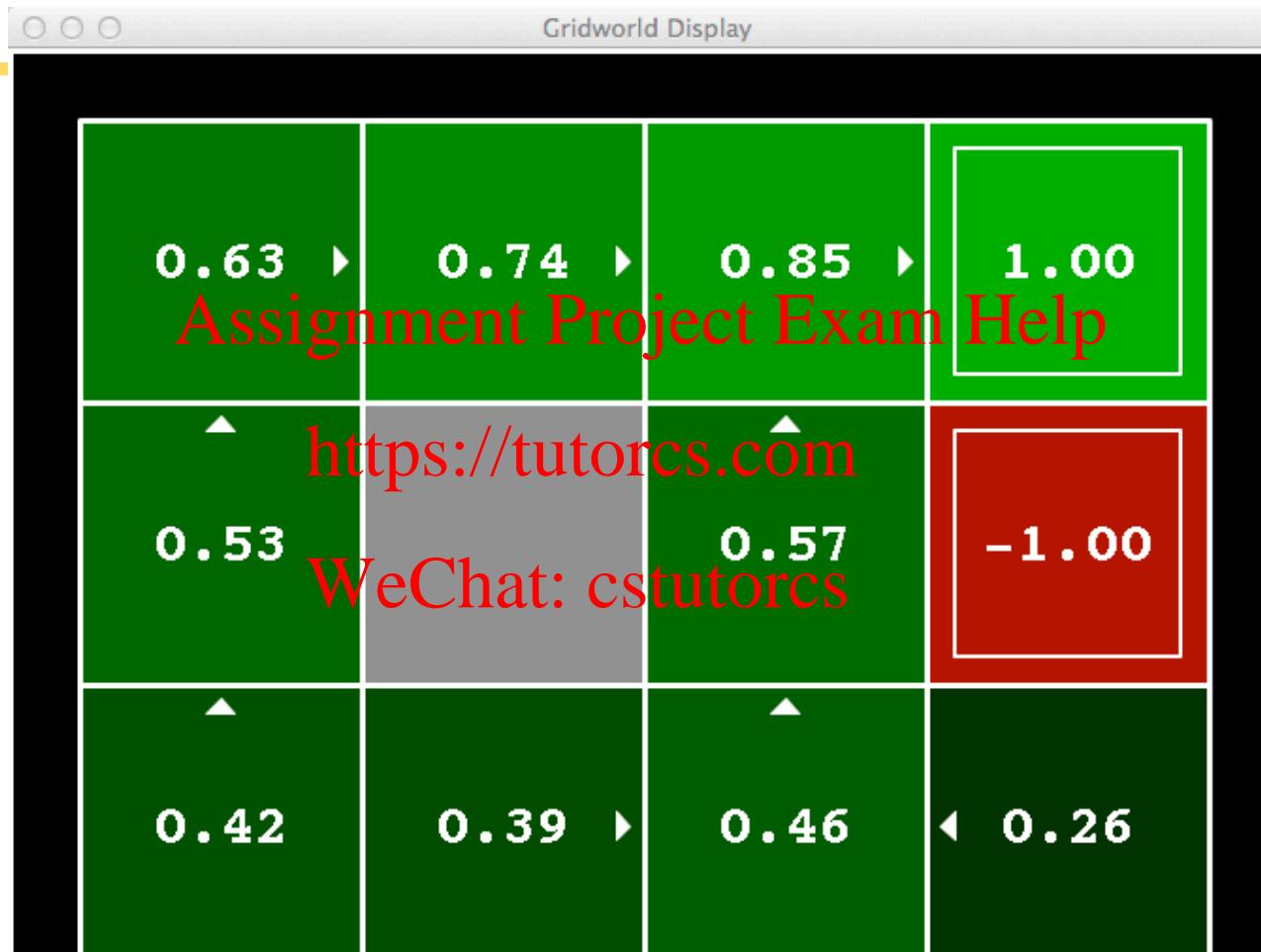
$k=6$



$k=7$



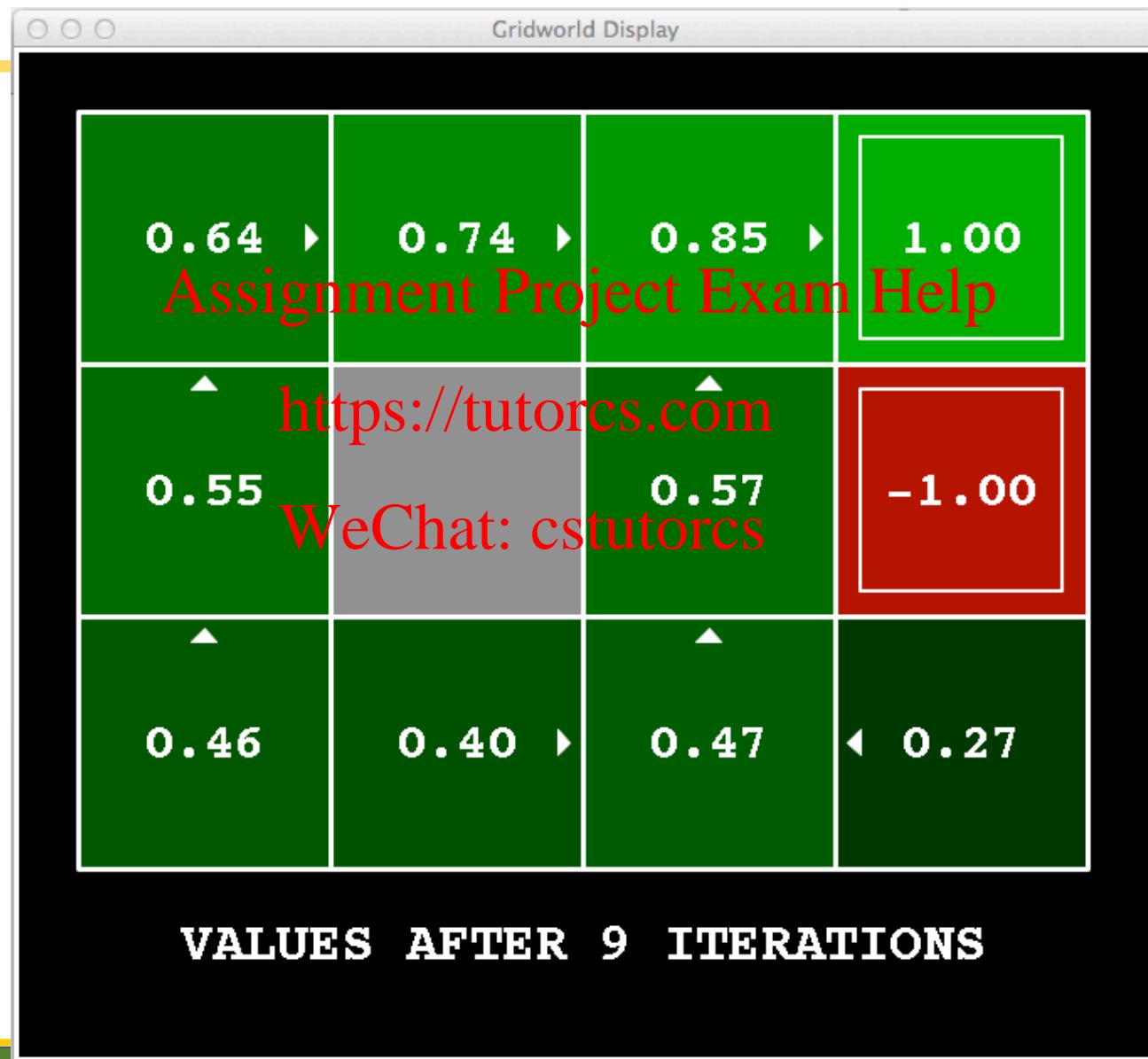
$k=8$



Noise = 0.2
Discount = 0.9
Living reward = 0



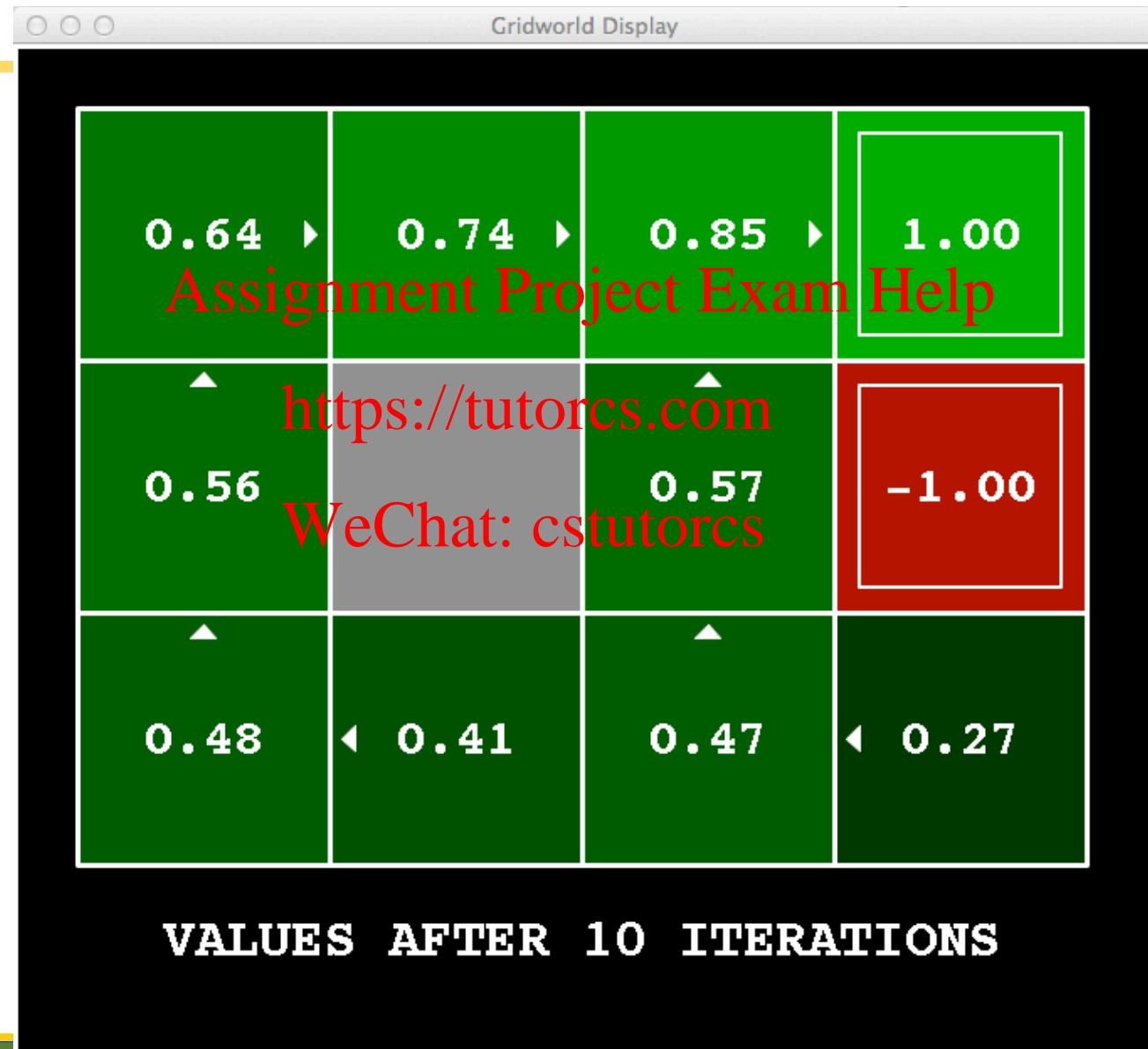
$k=9$



Noise = 0.2
Discount = 0.9
Living reward = 0



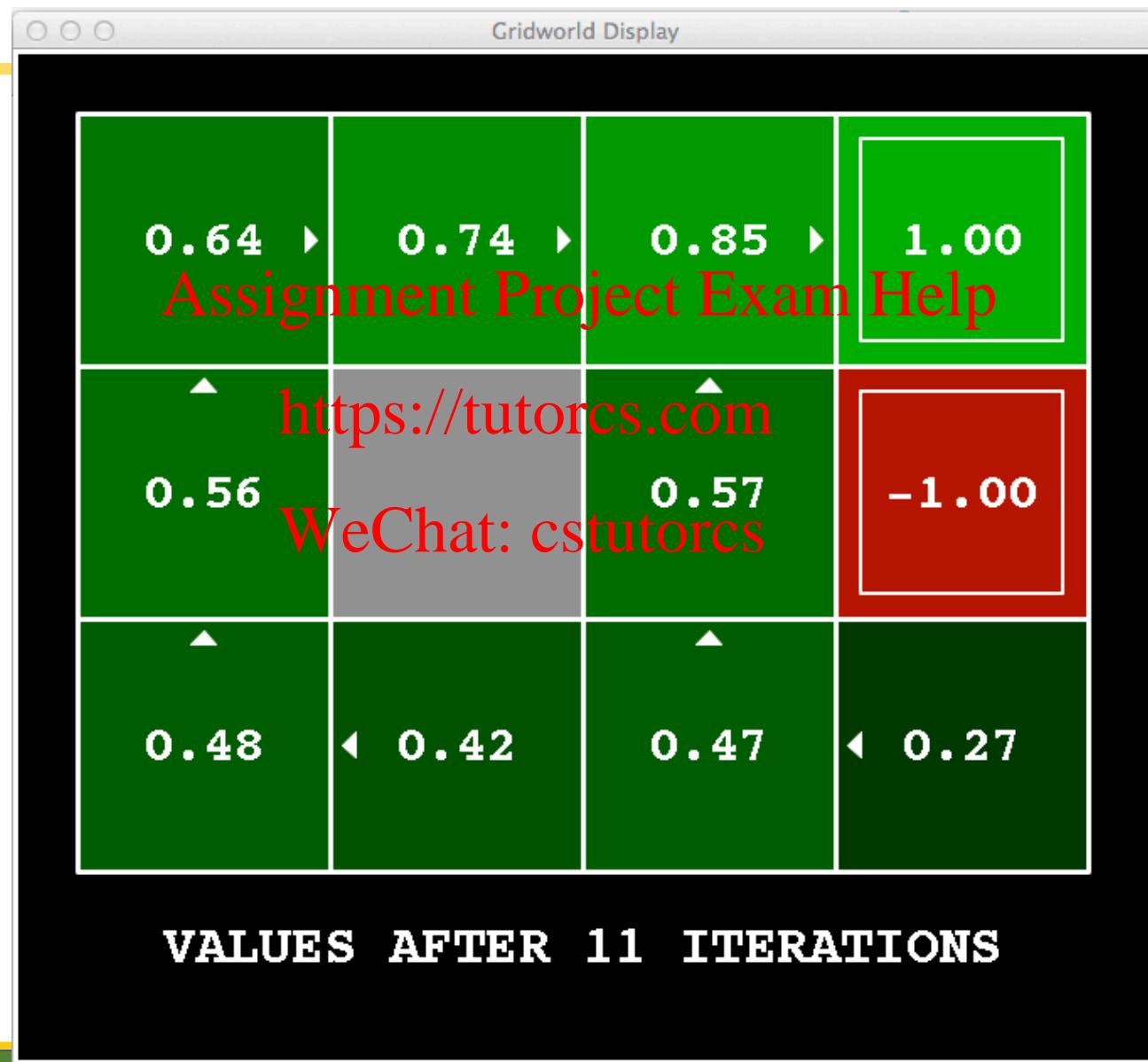
$k=10$



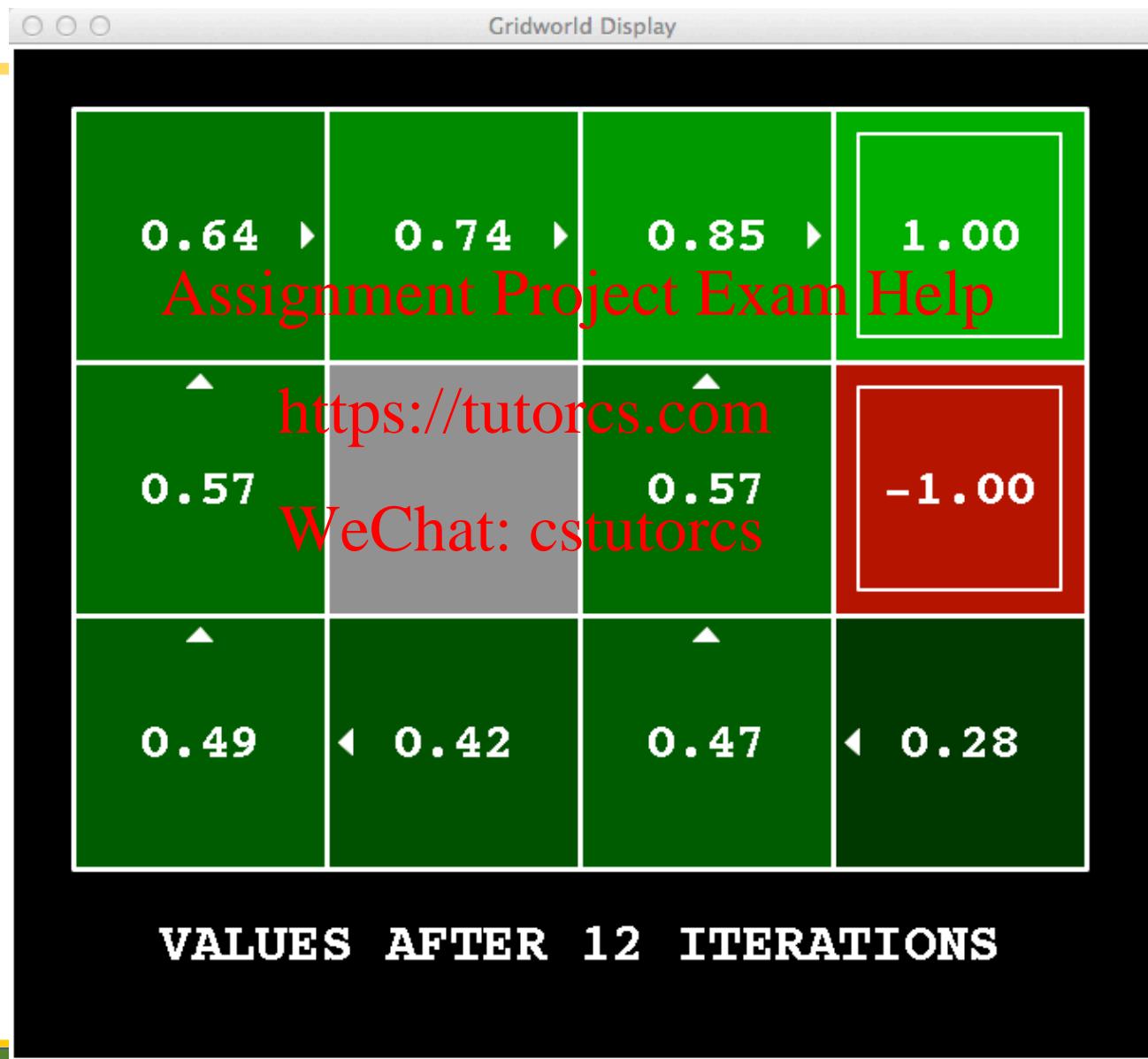
Noise = 0.2
Discount = 0.9
Living reward = 0



$k=11$



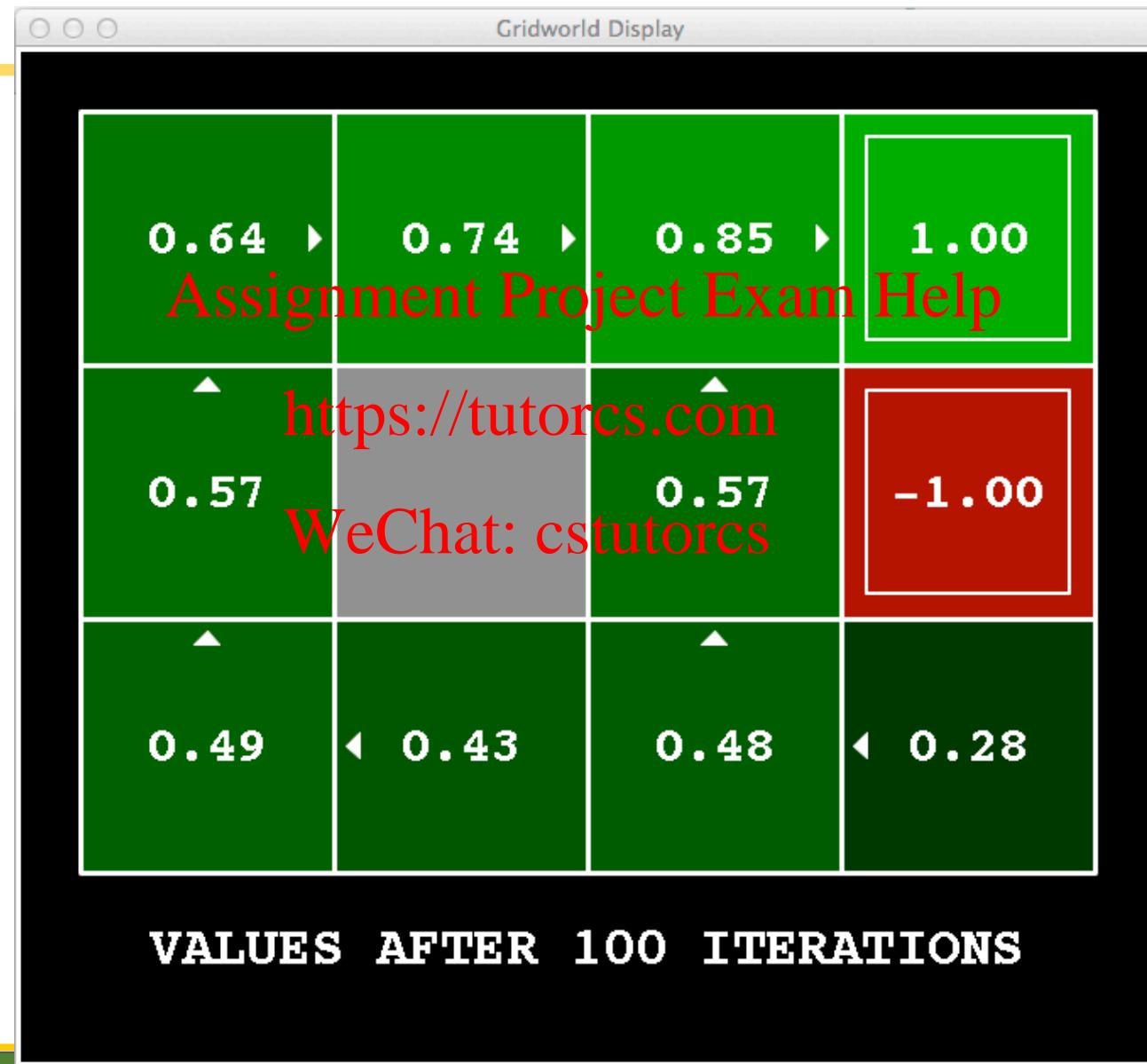
k=12



Noise = 0.2
Discount = 0.9
Living reward = 0



$k=100$

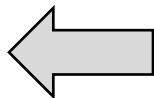


Noise = 0.2
Discount = 0.9
Living reward = 0

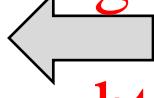


Computing Time-Limited Values

$$V_4(\text{blue car}) \quad V_4(\text{red car}) \quad V_4(\text{grey car})$$

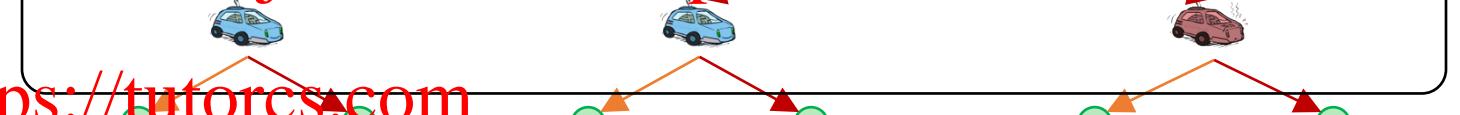


$$V_3(\text{blue car}) \quad V_3(\text{red car}) \quad V_3(\text{grey car})$$

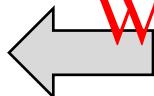


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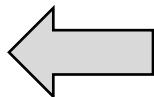
$$V_2(\text{blue car}) \quad V_2(\text{red car}) \quad V_2(\text{grey car})$$



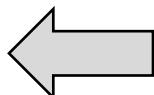
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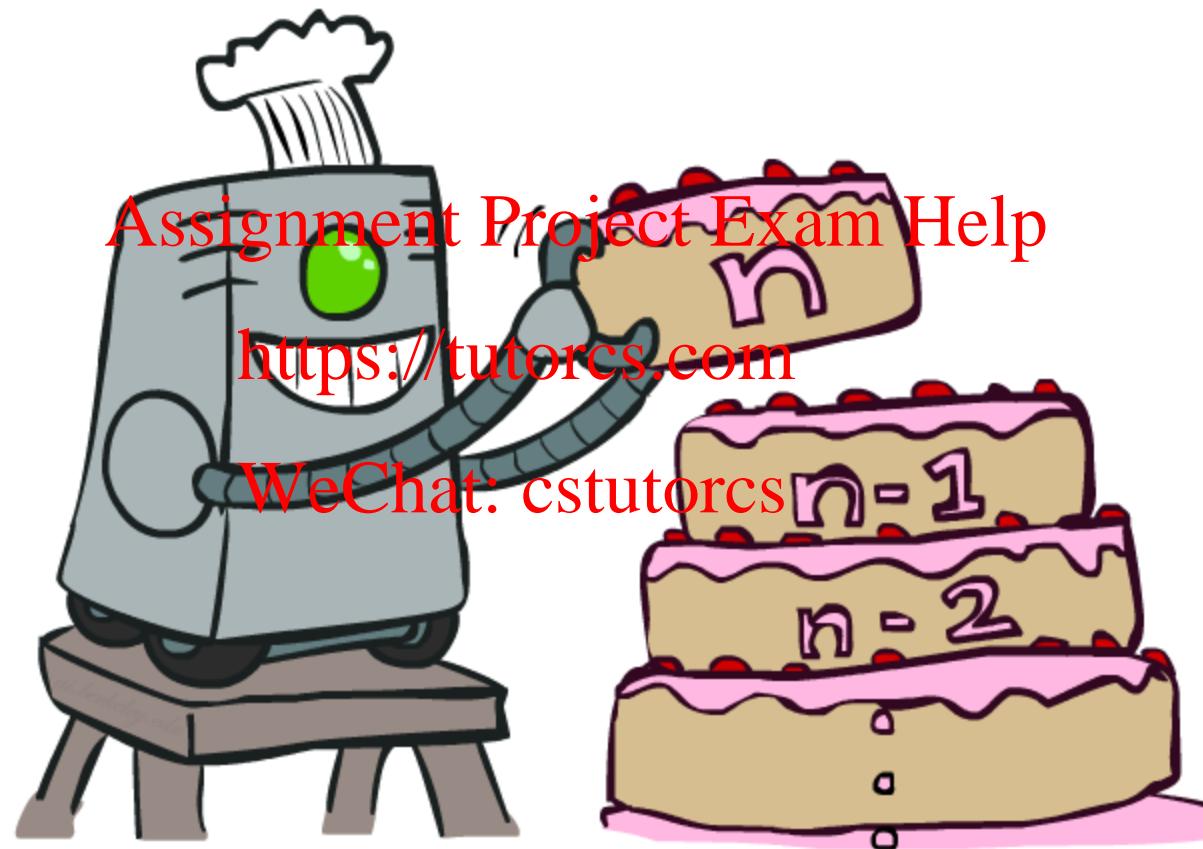
$$V_1(\text{blue car}) \quad V_1(\text{red car}) \quad V_1(\text{grey car})$$



$$V_0(\text{blue car}) \quad V_0(\text{red car}) \quad V_0(\text{grey car})$$



Value Iteration



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Value Iteration

- Start with $V_0(s) = 0$: no time steps left means an expected reward sum of zero
- Given vector of $V_k(s)$ values, do one ply of expectimax from each state:

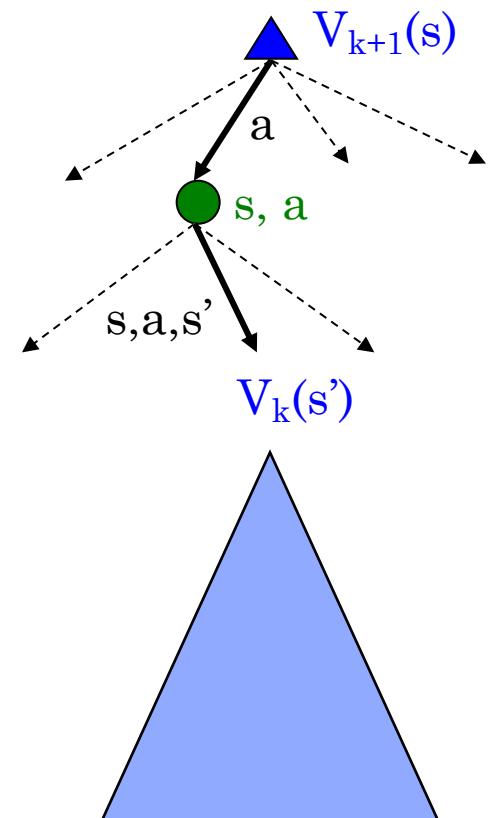
$$V_{k+1}(s) \leftarrow \max_a \sum_{s'} T(s, a, s') [R(s, a, s') + \gamma V_k(s')]$$

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- Repeat until convergence

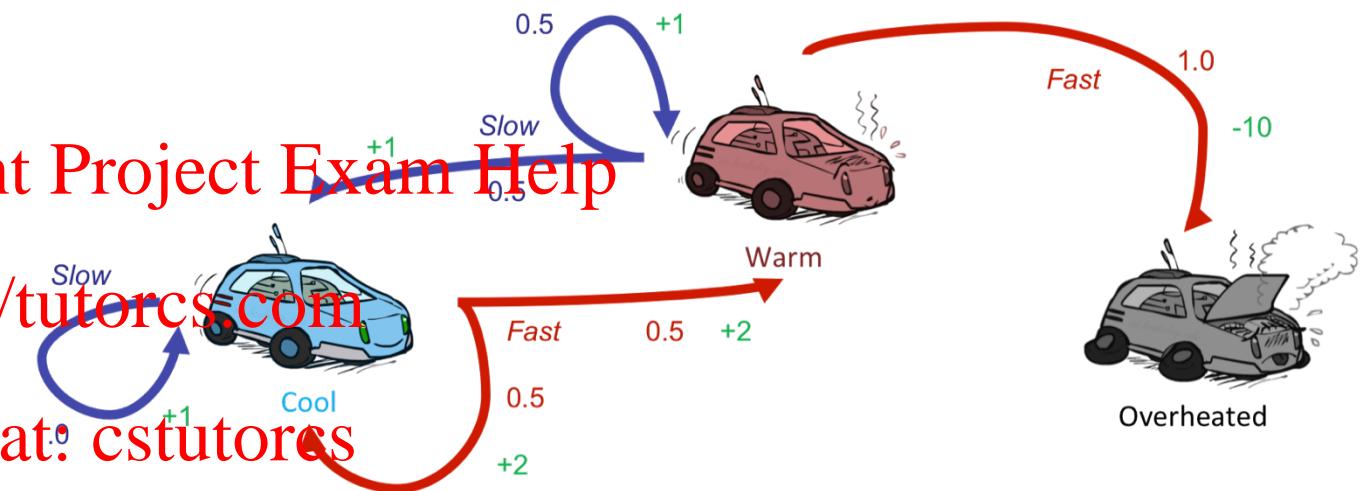
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- Complexity of each iteration: $O(S^2A)$
- Theorem: will converge to unique optimal values
 - Basic idea: approximations get refined towards optimal values
 - Policy may converge long before values do



Example: Value Iteration

V_2	3.5	2.5
	0	Assignment Project Exam Help
V_1	2	1
	0	WeChat: cstutorcs
V_0	0	0



Assume no discount!

$$V_{k+1}(s) \leftarrow \max_a \sum_{s'} T(s, a, s') [R(s, a, s') + \gamma V_k(s')]$$

Convergence*

- How do we know the V_k vectors are going to converge?

- Case 1: If the tree has maximum depth M , then V_M holds the actual untruncated values

- Case 2: If the discount is less than 1

- Sketch: For any state V_k and V_{k+1} can be viewed as depth $k+1$ expectimax results in nearly identical search trees
- The difference is that on the bottom layer, V_{k+1} has actual rewards while V_k has zeros
- That last layer is at best all R_{MAX}
- It is at worst R_{MIN}
- But everything is discounted by γ^k that far out
- So V_k and V_{k+1} are at most $\gamma^k \max |R|$ different
- So as k increases, the values converge

