

# Sparse Reward

Hung-yi Lee

# Sparse Reward

## Reward Shaping

# Reward Shaping



Take "Play",  
 $r_{t+1} = 1, r_{t+100} = -100$

Take "Study",  
 ~~$r_{t+1} = -1$~~ ,  $r_{t+100} = 100$

$r_{t+1} = 1$

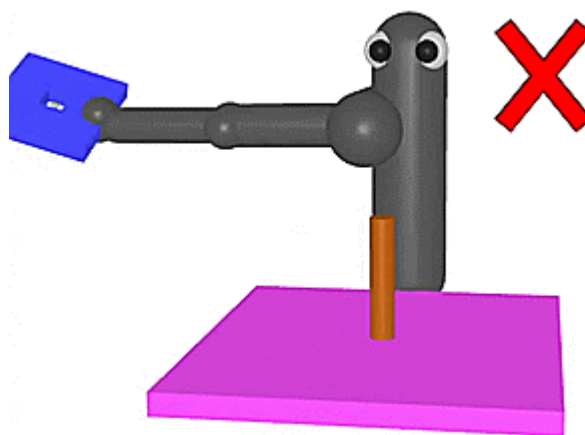
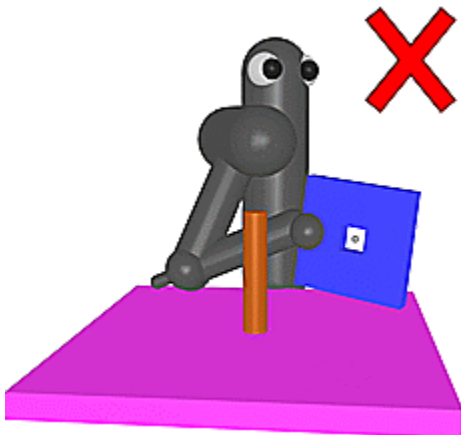


# Reward Shaping

## VizDoom

<https://openreview.net/forum?id=Hk3mPK5gg&notId=Hk3mPK5gg>

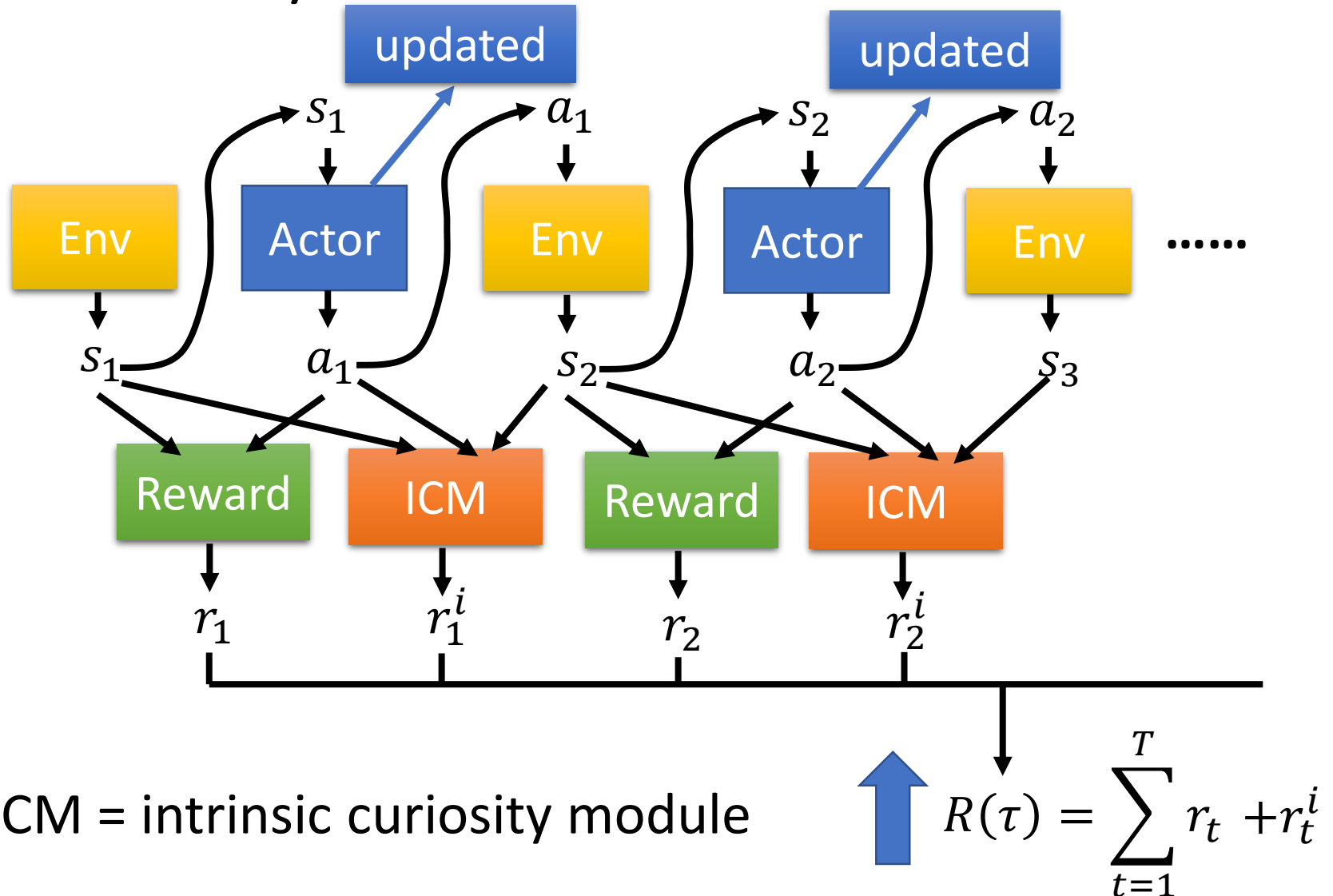
Parameters	Description	FlatMap	CIGTrack1
living	Penalize agent who just lives	-0.008 / action	
health_loss	Penalize health decrement	-0.05 / unit	
ammo_loss	Penalize ammunition decrement	-0.04 / unit	
health_pickup	Reward for medkit pickup	0.04 / unit	
ammo_pickup	Reward for ammunition pickup	0.15 / unit	
dist_penalty	Penalize the agent when it stays	-0.03 / action	
dist_reward	Reward the agent when it moves	9e-5 / unit distance	



Get reward,  
when closer  
  
Need domain  
knowledge

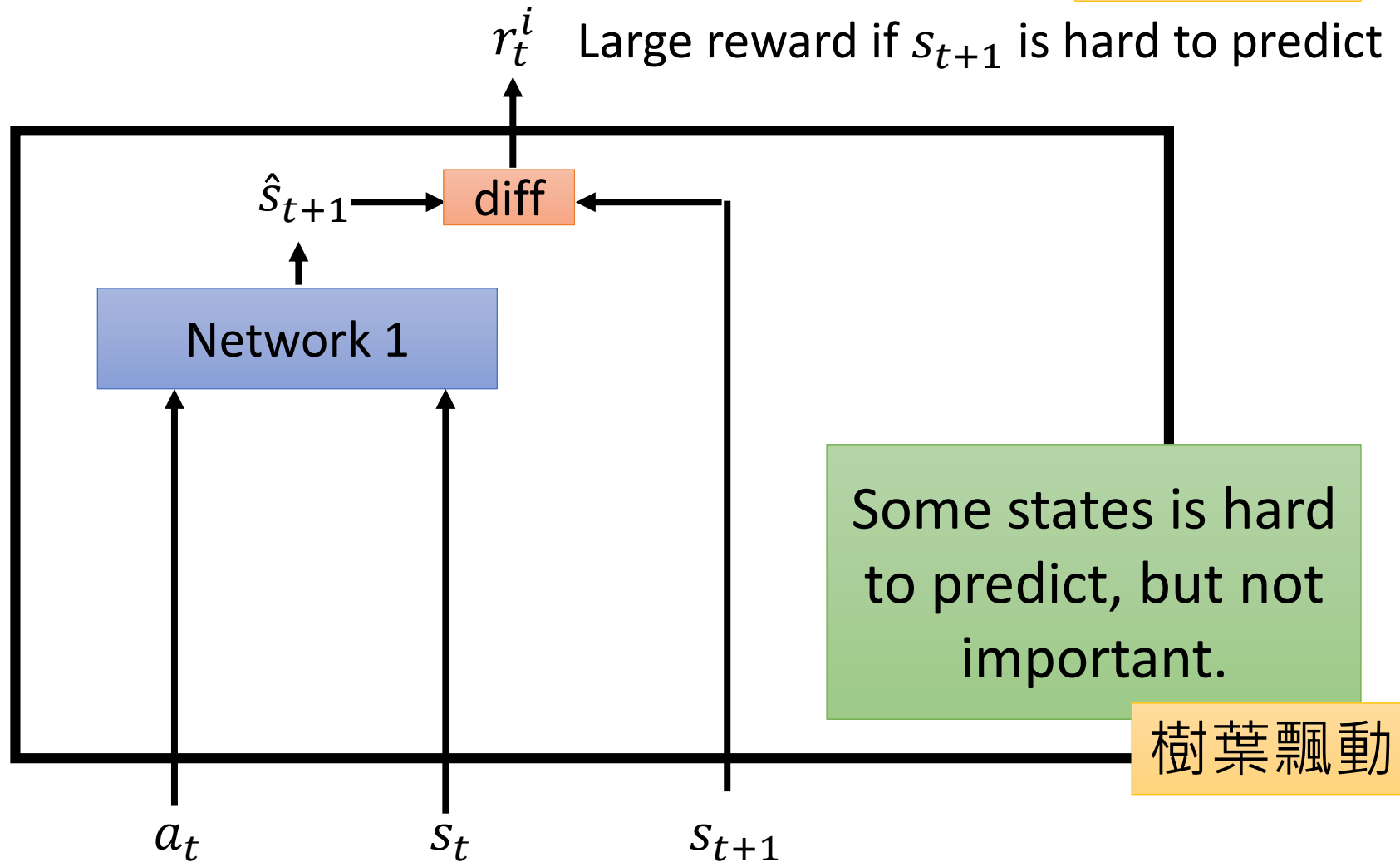
<https://openreview.net/pdf?id=Hk3mPK5gg>

# Curiosity

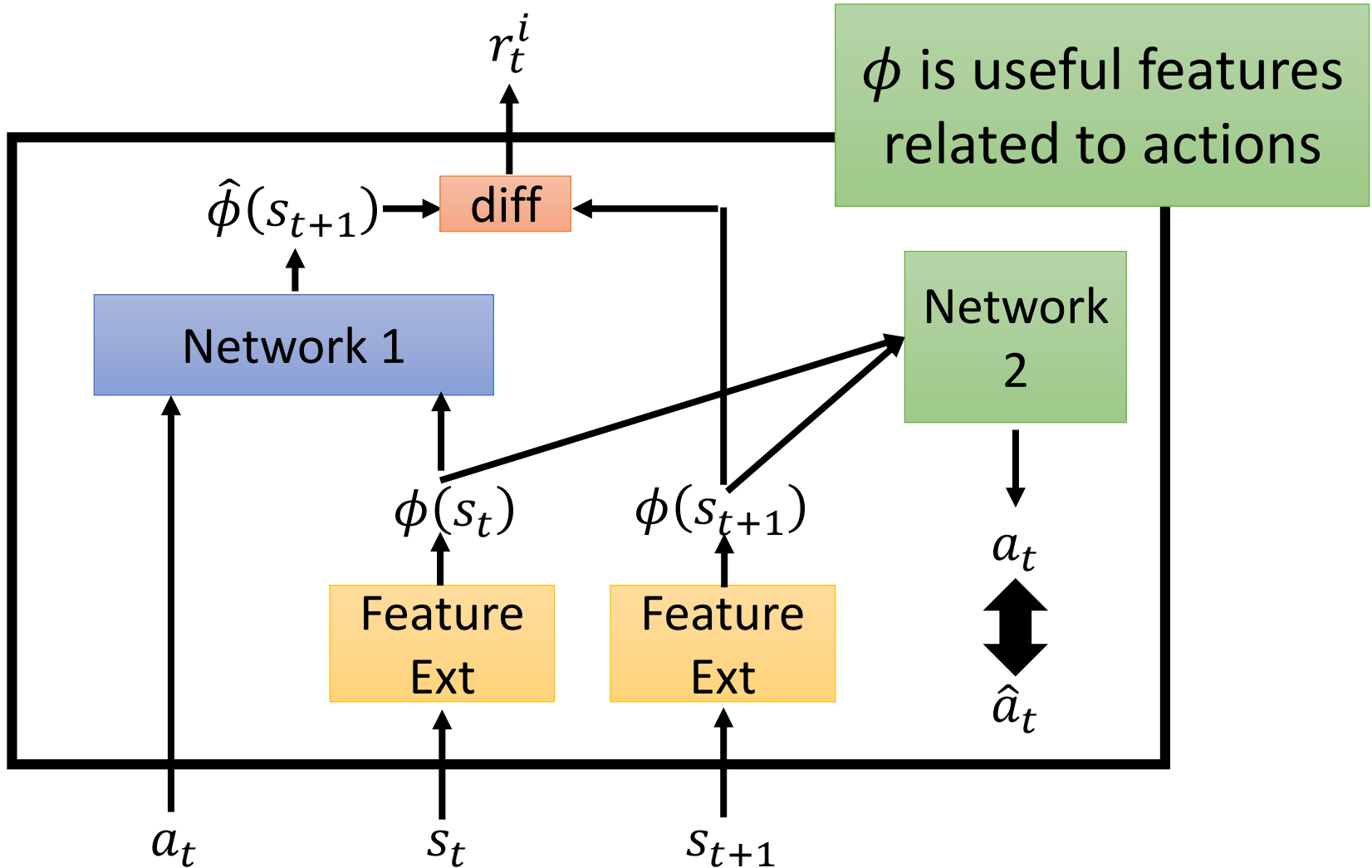


# Intrinsic Curiosity Module

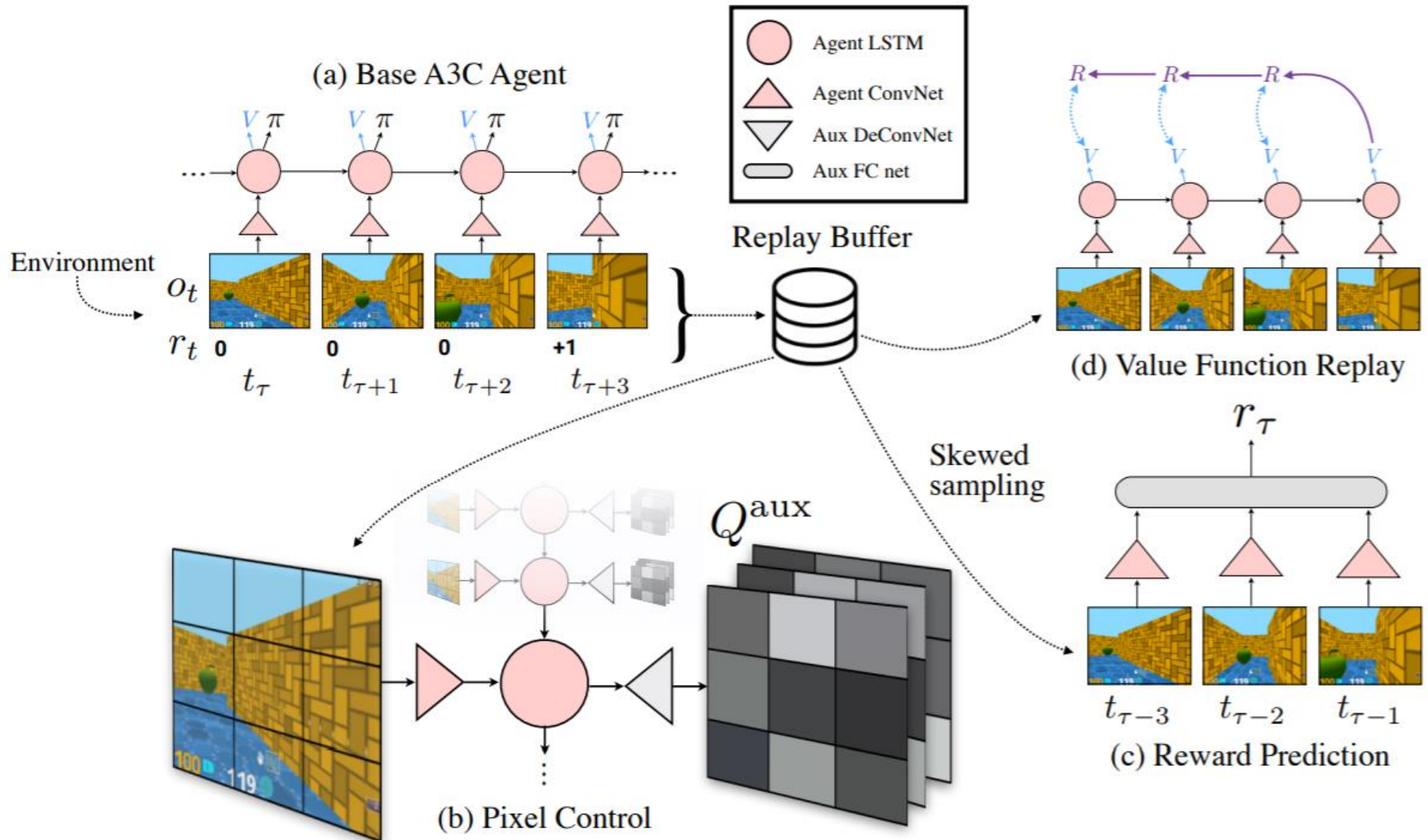
鼓勵冒險



# Intrinsic Curiosity Module

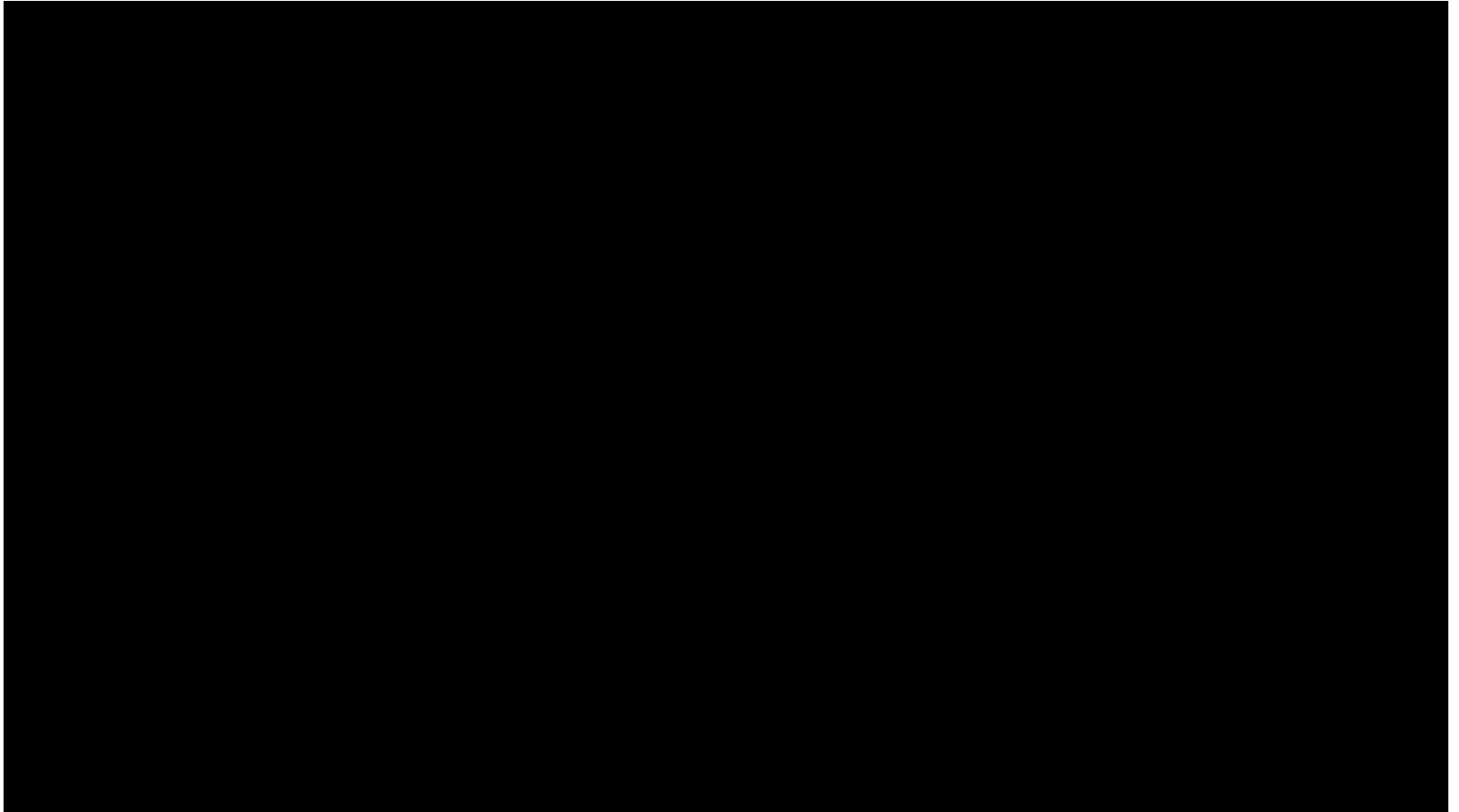


# Reward from Auxiliary Task





# Demo



# Sparse Reward

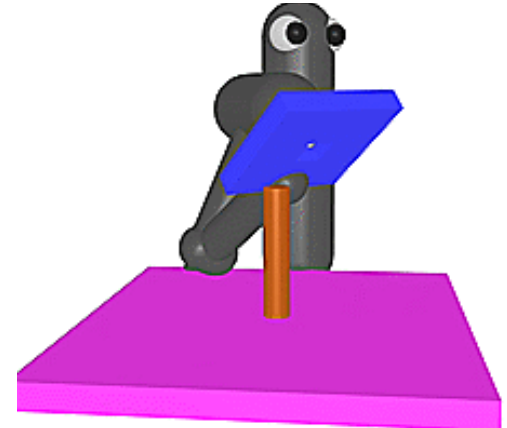
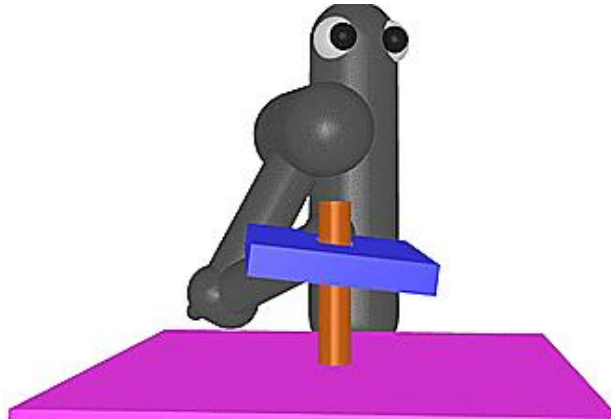
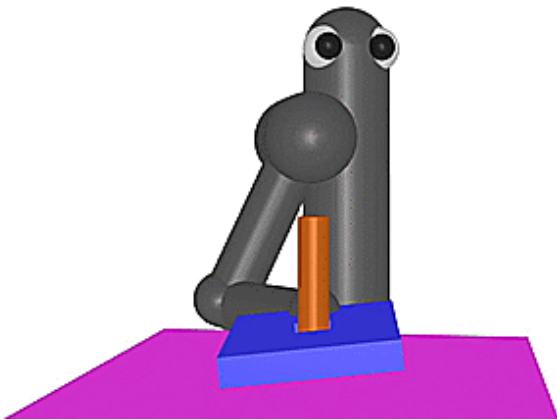
## Curriculum Learning

# Curriculum Learning

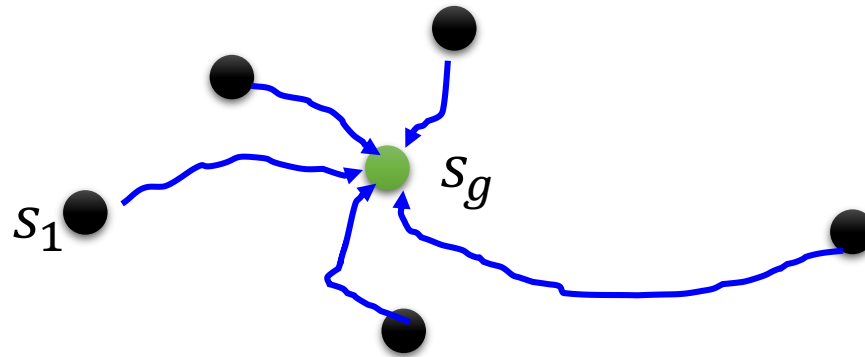
- Starting from simple training examples, and then becoming harder and harder.

## VizDoom

	Class 0	Class 1	Class 2	Class 3	Class 4	Class 5	Class 6	Class 7
Speed	0.2	0.2	0.4	0.4	0.6	0.8	0.8	1.0
Health	40	40	40	60	60	60	80	100

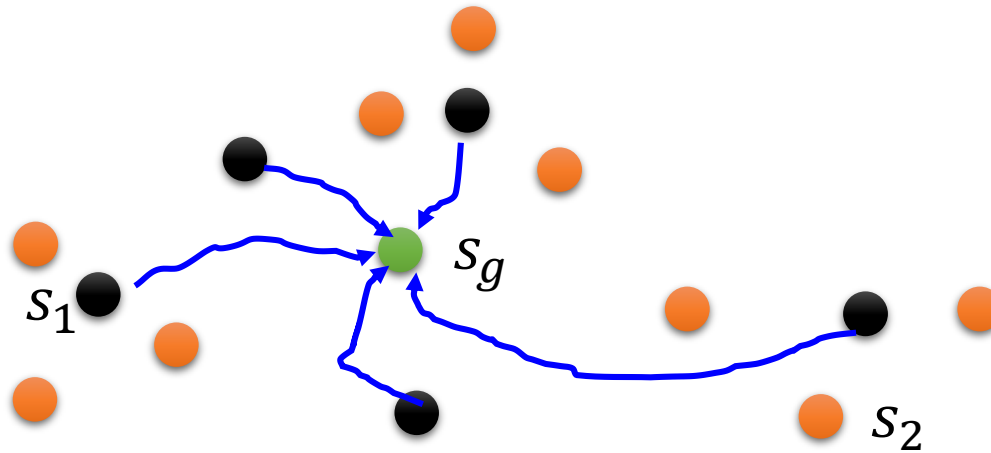


# Reverse Curriculum Generation



- Given a goal state  $s_g$ .
- Sample some states  $s_1$  “close” to  $s_g$
- Start from states  $s_1$ , each trajectory has reward  $R(s_1)$

# Reverse Curriculum Generation



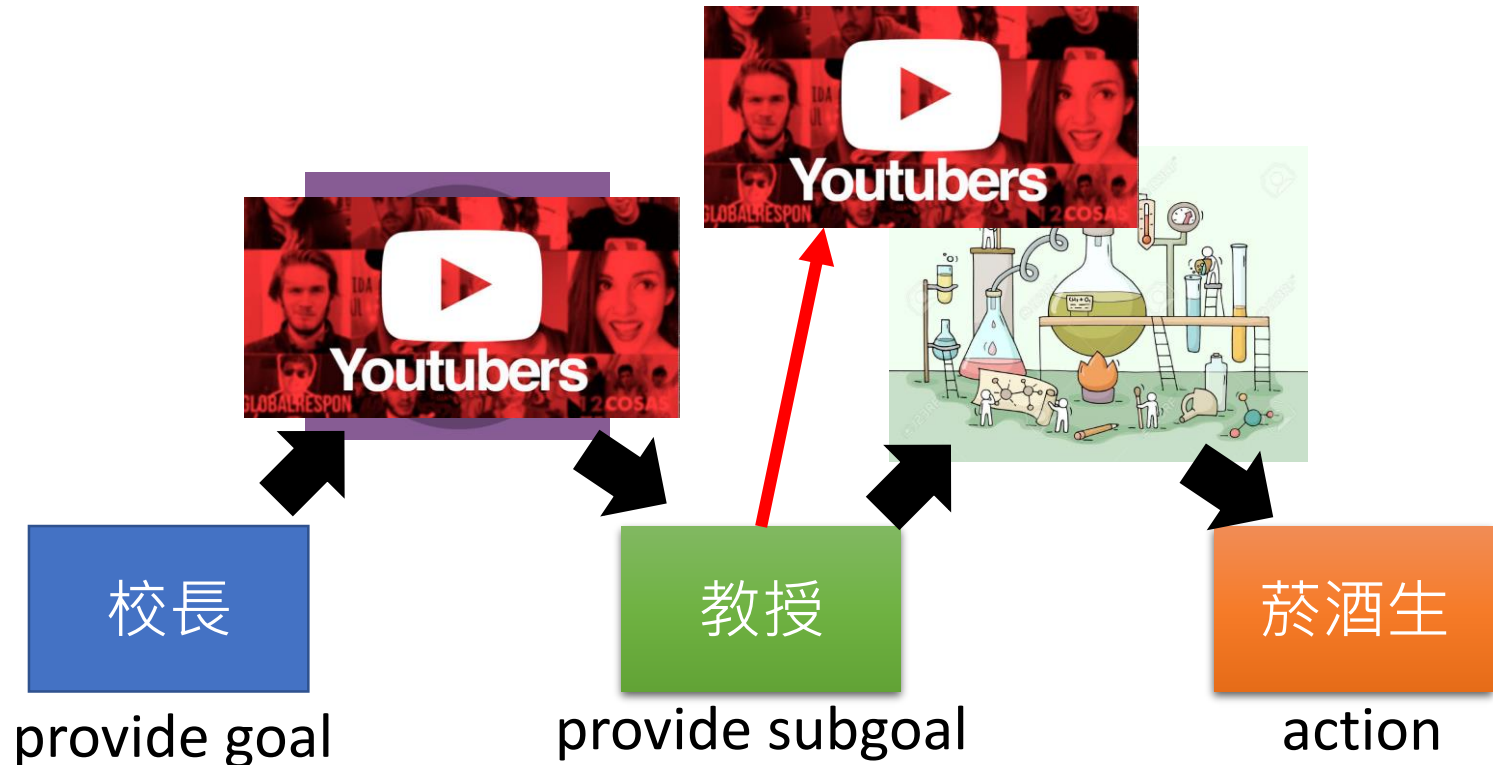
- Delete  $s_1$  whose reward is too large (already learned) or too small (too difficult at this moment)
- Sample  $s_2$  from  $s_1$ , start from  $s_2$

# Sparse Reward

## Hierarchical Reinforcement Learning

# Hierarchical RL

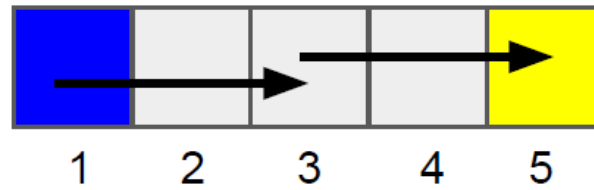
下面這個例子純屬虛構，  
跟真實的狀況完全不同



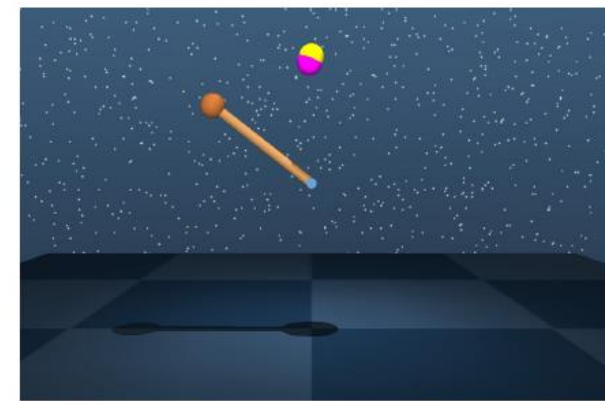
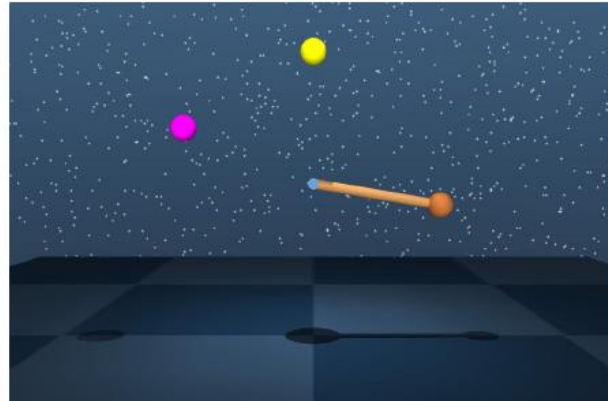
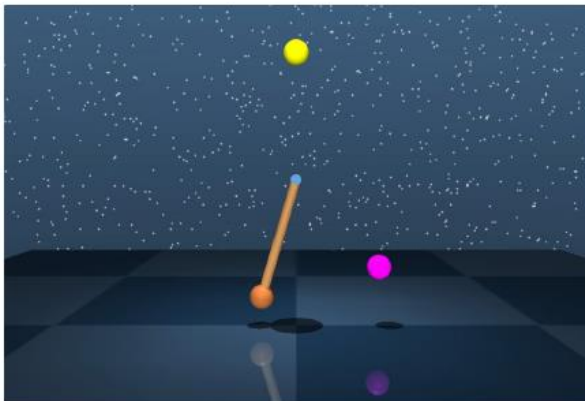
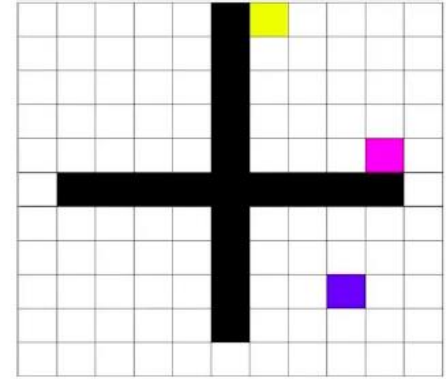
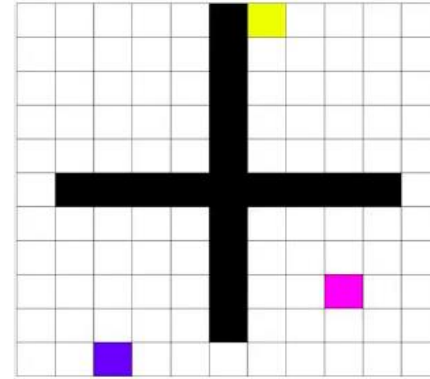
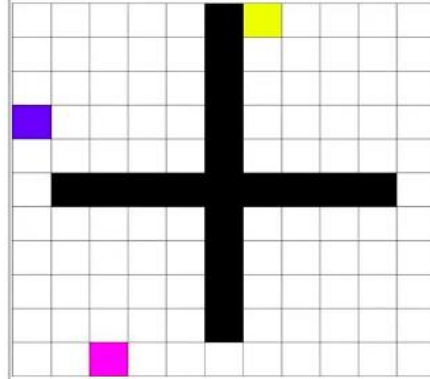
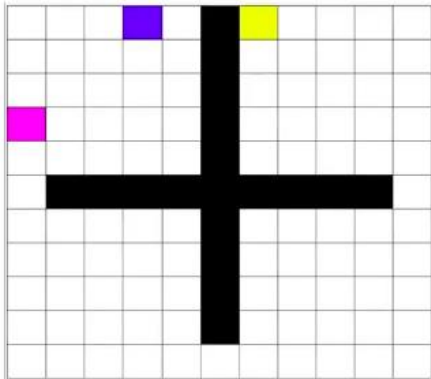
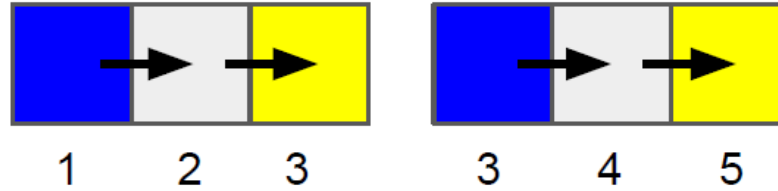
- If lower agent cannot achieve the goal, the upper agent would get penalty.
- If an agent get to the wrong goal, assume the original goal is the wrong one.

<https://arxiv.org/abs/1805.08180>

High-Level



Low-Level





# Acknowledgement

- 感謝芮祥麟博士發現課程網頁上拼字的錯誤