

Variance Reduction in Policy Gradient

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Recap: policy gradient for contextual bandits

[Online] Stochastic k -armed contextual bandit

Stochastic k -armed contextual bandit

- 1 Environment samples **context** and **rewards vector** jointly, iid, for each round:

$$(X, R), (X_1, R_1), \dots, (X_T, R_T) \in \mathcal{X} \times \mathbb{R}^k \text{ i.i.d. from } P,$$

where $R_t = (R_t(1), \dots, R_t(k)) \in \mathbb{R}^k$.

- 2 For $t = 1, \dots, T$,

- 1 Our algorithm **selects action** $A_t \in \mathcal{A} = \{1, \dots, k\}$ based on X_t and history

$$\mathcal{D}_t = \left((X_1, A_1, R_1(A_1)), \dots, (X_{t-1}, A_{t-1}, R_{t-1}(A_{t-1})) \right).$$

- 2 Our algorithm **receives reward** $R_t(A_t)$.

- We **never observe** $R_t(a)$ for $a \neq A_t$.

Contextual bandit policies

- A contextual bandit policy at round t
 - gives a conditional distribution over the action A_t to be taken
 - conditioned on the history \mathcal{D}_t and the **current context** X_t .
- In this module, we consider policies parameterized by θ : $\pi_\theta(a | x)$, for $\theta \in \mathbb{R}^d$.
- We denote the θ used at round t by θ_t , which will depend on \mathcal{D}_t .
- At round t , action $A_t \in \mathcal{A} = \{1, \dots, k\}$ is chosen according to

$$\mathbb{P}(A_t = a | X_t = x, \mathcal{D}_t) = \pi_{\theta_t}(a | x).$$

Example: multinomial logistic regression policy

- An example parameterized policy:

$$\pi_{\theta}(a | x) = \frac{\exp(\theta^T \phi(x, a))}{\sum_{a'=1}^k \exp(\theta^T \phi(x, a'))},$$

where $\phi(x, a) : \mathcal{X} \times \mathcal{A} \rightarrow \mathbb{R}^d$ is a joint feature vector.

- And $\theta^T \phi(x, a)$ can be replaced by a more general $g_{\theta} : \mathcal{X} \times \mathcal{A} \rightarrow \mathbb{R}$.
- The whole conditional distribution $\pi_{\theta}(a | x)$ can also be represented as a neural network with a softmax output.
- The differentiability w.r.t. θ is key to a policy gradient method.

How to update the policy?

- Objective function for policy gradient:

$$J(\theta) := \mathbb{E}_{\theta} [R(A)].$$

- Idealized policy gradient is to iteratively update θ as:

$$\theta_{t+1} \leftarrow \theta_t + \eta \nabla J(\theta_t).$$

- Policy gradient theorem from last module gives an unbiased estimate of $\nabla J(\theta_t)$.

Unbiased estimate for the gradient

- Consider round t of SGD for optimizing $J(\theta)$.
- We play A_t from $\pi_{\theta_t}(a | X_t)$ and record $(X_t, A_t, R_t(A_t))$.
- To update θ_t , we need an unbiased estimate of $\nabla J(\theta_t)$.
- Last time we showed that

$$\mathbb{E}_{\theta_t} [R_t(A_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)] = \nabla_{\theta} J(\theta_t)$$

- Suggests the following iterative update:

$$\theta_{t+1} \leftarrow \theta_t + \eta R_t(A_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t).$$

- This is the basic **policy gradient method**.

Using a baseline

Subtracting a baseline from reward

- Our objective function is

$$J(\theta) = \mathbb{E}_{\theta} [R(A)].$$

- Suppose we introduce a new reward vector $R_0 = R - b$, for constant $b \in \mathbb{R}$.
- Then

$$J_b(\theta) = \mathbb{E}_{\theta} (R_0(A)) = \mathbb{E}_{\theta} (R(A)) - b.$$

- Obviously, $J(\theta)$ and $J_b(\theta)$ have the same maximizer θ^* .
- And $\nabla_{\theta} J(\theta) = \nabla_{\theta} J_b(\theta)$.

Policy gradient with a baseline

- If we just plug in the shift to our gradient estimators, we get:

$$\begin{aligned} J(\theta): \quad \theta_{t+1} &\leftarrow \theta_t + \eta R_t(A_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) \\ J_b(\theta): \quad \theta_{t+1} &\leftarrow \theta_t + \eta (R_t(A_t) - b) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) \end{aligned}$$

where b is called the **baseline**.

- The updates are different, so we'll get different optimization paths.
- Is $(R_t(A_t) - b) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)$ still unbiased for $\nabla J(\theta)$?
- Doesn't really look like it.
- But we'll show that it is, even when we allow a random baseline $B_t = f(\mathcal{D}_t, X_t)$.
- The hope is to find a B_t that reduces the variance of the gradient estimate,
 - getting us to a better policy, faster.

The score has zero expectation

- Let $p(a; \theta)$ be a parametric distribution on a finite set \mathcal{A} .
- The **score function** is defined as $s(a, \theta) = \nabla_{\theta} \log p(a; \theta)$.
- Then $\mathbb{E}_{A \sim p(a; \theta)} [s(A, \theta)] = 0$ for any θ .
- **Proof:** (assuming differentiability as needed)

$$\begin{aligned}\mathbb{E}_{A \sim p(a; \theta)} [s(A, \theta)] &= \mathbb{E}_{A \sim p(a; \theta)} [\nabla_{\theta} \log p(a; \theta)] \\&= \mathbb{E}_{A \sim p(a; \theta)} \left[\frac{\nabla_{\theta} p(a; \theta)}{p(a; \theta)} \right] \\&= \sum_{a \in \mathcal{A}} p(a; \theta) \left[\frac{\nabla_{\theta} p(a; \theta)}{p(a; \theta)} \right] = \sum_{a \in \mathcal{A}} \nabla_{\theta} p(a; \theta) \\&= \nabla_{\theta} \left[\sum_{a \in \mathcal{A}} p(a; \theta) \right] = \nabla_{\theta} [1] = 0\end{aligned}$$

Estimate with baseline is unbiased

- Allow θ_t and the baseline B_t at round t to depend on \mathcal{D}_t and X_t :

$$\begin{aligned} B_t &= f(\mathcal{D}_t, X_t) \quad \text{for some function } f, \text{ and let} \\ \theta_t &= g(\mathcal{D}_t) \quad \text{for some function } g. \end{aligned}$$

- So

$$\begin{aligned} &\mathbb{E}[B_t \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)] \\ &= \mathbb{E}[\mathbb{E}[B_t \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) | \mathcal{D}_t, X_t]] \quad \text{inner expectation over } A_t \sim \pi_{\theta_t}(\cdot | X_t) \\ &= \mathbb{E}[B_t \mathbb{E}[\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) | \mathcal{D}_t, X_t]] \quad \text{taking out what is known} \\ &= \mathbb{E}[B_t 0] = 0. \end{aligned}$$

- Therefore $(R_t(A_t) - B_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)$ is an unbiased estimate of $\nabla J(\theta)$.
 - for any choice of f and g above.

- Let's show $\mathbb{E}[\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) | \mathcal{D}_t, X_t] = 0$ very explicitly. First, the only thing random in the expectation is $A_t \sim \pi_{\theta_t}(\cdot | X_t)$. Note that θ_t is generally random, via its dependence on \mathcal{D}_t , but we're conditioning on \mathcal{D}_t , so θ_t is constant here.
- Previously, we showed $\mathbb{E}_{A \sim p(a; \theta)} [s(A, \theta)] = 0$ for any θ , where $s(a, \theta) = \nabla_{\theta} \log p(a; \theta)$. We'll try to put things in these terms...
- Define $p(a; \theta, x) = \pi_{\theta}(a | x)$, which gives a distribution on \mathcal{A} for every $\theta \in \Theta$ and $x \in \mathcal{X}$. Define the corresponding score function as $s(a, \theta; x) = \nabla_{\theta} \log p(a; \theta, x)$. Then we know $\mathbb{E}_{A \sim p(a; \theta, x)} [s(A, \theta; x)] = 0$ for every θ and x , which we apply in the last step below. Let

$$\begin{aligned}
 r(d, x) &:= \mathbb{E}[\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) | \mathcal{D}_t = d, X_t = x] \\
 &= \mathbb{E}[\nabla_{\theta} \log p(A_t; \theta_t, x) | \mathcal{D}_t = d, X_t = x] \\
 &= \mathbb{E}[s(A_t, \theta_t; x) | \mathcal{D}_t = d, X_t = x] \\
 &= \mathbb{E}[s(A_t, g(d); x) | \mathcal{D}_t = d, X_t = x] \quad (\text{only } A_t \text{ is random}) \\
 &= \mathbb{E}_{A_t \sim p(a; g(d), x)} [s(A_t, g(d); x)] \\
 &= 0.
 \end{aligned}$$

So $r(\mathcal{D}_t, X_t) = \mathbb{E}[\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) | \mathcal{D}_t, X_t] = 0$.

What to use for the baseline?

- In round t , our unbiased estimate of $\nabla_{\theta} J(\theta_t)$ is

$$(R_t(A_t) - B_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t).$$

- We're trying to “reduce the variance” of this estimate.
- But what is the “variance”?
- This expression is generally a **vector**.
- There is no scalar “variance” we can just try to minimize.
- We'll revisit this shortly...

Basic approach to the baseline

- The easiest thing to use for a baseline is

$$B_t = \frac{1}{t-1} \sum_{i=1}^{t-1} R_i(A_i).$$

- Think B_t as a **value estimate** for policy $\pi_{\theta_t}(a | x)$: $B_t \approx \mathbb{E}_{\theta_t}[R_t(A_t)]$.
- It should make some rewards positive and some rewards negative.
- In practice, it's usually much better than $B_t \equiv 0$.

Input-dependent baseline

- What if rewards R_t are generally smaller for some inputs X_t than others?
- We can try to choose $B_t \approx \mathbb{E}_{\theta_t} [R(A_t) \mid X_t]$.
- Learn $\hat{r}_t(x) \approx \mathbb{E}_{\theta_t} [R_t(A_t) \mid X_t = x]$ from history \mathcal{D}_t .
- Use $B_t = \hat{r}_t(X_t)$ as a baseline for round t .
- We can learn $\hat{r}_t(x)$ in an online manner, at the same time as we learn our policy.
 - e.g. in t 'th round take a gradient step to reduce $(R_t(A_t) - \hat{r}_t(X_t))^2$.
- This is an approach suggested in Sutton's book [SB18, Sec 13.4].

“Optimal” baseline

“Optimal” baseline

- Our gradient estimator is $(R_t(A_t) - B_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)$.
- This a vector, so it's not clear what it means to minimize the variance.
- Let's allow a different baseline $B_t(\alpha)$ for each entry of the gradient estimate.
 - (We did this for the multiarmed bandit in the previous module.)
- Now we can attempt to minimize the variance for each entry separately.

The entry variance

- Define

$$G_t^j = [\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)]_j.$$

- That is, G_t^j is the j 'th entry of the score at round t .
- Let's consider the variance of the j th entry of our estimator with baseline b :

$$\begin{aligned} V_j &:= \text{Var} \left([(R_t(A_t) - b) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)]_j \right) \\ &= \text{Var} \left((R_t(A_t) - b) G_t^j \right) \\ &= \mathbb{E} \left[(R_t(A_t) - b)^2 \left(G_t^j \right)^2 \right] - \left[\mathbb{E} (R_t(A_t) - b) G_t^j \right]^2 \\ &= \mathbb{E} (R_t(A_t) - b)^2 \left(G_t^j \right)^2 - \left[\mathbb{E} \left[R_t(A_t) G_t^j \right] \right]^2 \end{aligned}$$

“Optimal” baselines

- Differentiating V_j w.r.t. b :

$$\begin{aligned}V_j &= \mathbb{E} (R_t(A_t) - b)^2 (G_t^j)^2 - \left[\mathbb{E} \left[R_t(A_t) G_t^j \right] \right]^2 \\ \frac{dV_j}{db} &= \frac{d}{db} \left(\mathbb{E} \left[R_t(A_t)^2 (G_t^j)^2 \right] + b^2 \mathbb{E} (G_t^j)^2 - 2b \mathbb{E} R_t(A_t) (G_t^j)^2 \right) \\ &= 2b \mathbb{E} (G_t^j)^2 - 2 \mathbb{E} R_t(A_t) (G_t^j)^2\end{aligned}$$

- Solving for b in $\frac{dV_j}{db} = 0$:

$$b_t^j := \frac{\mathbb{E} \left[R_t(A_t) (G_t^j)^2 \right]}{\mathbb{E} \left[(G_t^j)^2 \right]}$$

“Optimal baselines”

- So estimate for the j 'th entry should ideally use baseline b_t^j .
- We can try to estimate the expectations from the logs:

$$\mathbb{E} \left[R_t(A_t) \left(G_t^j \right)^2 \right] \approx \frac{1}{t-1} \sum_{i=1}^{t-1} R_i(A_i) \left(G_i^j \right)^2$$
$$\mathbb{E} \left[\left(G_t^j \right)^2 \right] \approx \frac{1}{t-1} \sum_{i=1}^{t-1} \left(G_i^j \right)^2.$$

- This derivation is based on [Berkeley's CS 285: Lecture 5, Slide 19](#), but their slide is quite vague on specifics. They don't seem to acknowledge that the gradient is a vector or that they'll need a different baseline for each entry. They also don't indicate how to estimate the expectations. Their interpretation of the resulting b_t^j in that slide is that it's "just expected reward, but weighted by gradient magnitudes!". More references are given on the resources slide at the end of this deck.
- If you're after an "optimal" **scalar** baseline, you could try minimizing the trace of the covariance matrix or $\| (R_t(A_t) - B_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t) \|_2^2$.

“Optimal baselines” putting it together

- Let θ_t^j denote the j 'th entry of θ_t .
- Update step at round t with these baselines is

$$\theta_{t+1}^j \leftarrow \theta_t^j + \eta \left(R_t(A_t) - B_t^j \right) [\nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t)]_j,$$

where

$$B_t^j = \left[\frac{1}{t-1} \sum_{i=1}^{t-1} R_i(A_i) \left(G_i^j \right)^2 \right] / \frac{1}{t-1} \sum_{i=1}^{t-1} \left(G_i^j \right)^2$$
$$G_i^j = [\nabla_{\theta} \log \pi_{\theta_t}(A_i | X_i)]_j$$

Actor-Critic methods

Recall the policy gradient derivation

- Recall the following formulation of the value function:

$$\begin{aligned}\mathbb{E}_{\theta} [R(A)] &= \mathbb{E}_X [\mathbb{E}_{A|X \sim \theta} [\mathbb{E}_{R|X} [R(A) | A, X] | X]] \\ &= \mathbb{E}_X \left[\sum_{a=1}^k \pi_{\theta}(a | X) \mathbb{E}_{R|X} [R(A) | A = a, X] \right]\end{aligned}$$

- So

$$\nabla_{\theta} \mathbb{E}_{\theta} [R(A)] = \mathbb{E}_X \left[\sum_{a=1}^k \nabla_{\theta} [\pi_{\theta}(a | X)] \mathbb{E}_{R|X} [R(A) | A = a, X] \right]$$

- In PG, we use a “clever trick” to get an unbiased estimate of $\nabla \mathbb{E}_{\theta} [R(A)]$ from $(X_t, A_t, R_t(A_t))$.

Plug-in a value estimate

- We have

$$\nabla_{\theta} \mathbb{E}_{\theta} [R(A)] = \mathbb{E}_X \left[\sum_{a=1}^k \nabla_{\theta} [\pi_{\theta}(a | X)] \mathbb{E}_{R|X} [R(A) | A = a, X] \right]$$

- Suppose we had $\hat{r}(x, a) \approx \mathbb{E} [R(A) | A = a, X = x]$.
- Then we get

$$\begin{aligned} \nabla_{\theta} \mathbb{E}_{\theta} [R(A)] &\approx \mathbb{E}_X \left[\sum_{a=1}^k \nabla_{\theta} [\pi_{\theta}(a | X)] \hat{r}(X, a) \right] \\ &\approx \sum_{a=1}^k \nabla_{\theta} [\pi_{\theta}(a | X_t)] \hat{r}(X_t, a) \end{aligned}$$

- The last step is a one-sample Monte Carlo estimate for \mathbb{E}_X .

Online update of value estimator

- Parametrize value estimator: $\hat{r}_w(x, a)$.
- We'll fit w by SGD on square loss:

$$\nabla_w (\hat{r}_w(X, A) - R(A))^2 = 2(\hat{r}_w(X, A) - R(A)) \nabla_w \hat{r}_w(X, A).$$

- This is the step direction, and we can absorb the 2 into the step size multiplier.
- So value estimator update is

$$w_{t+1} \leftarrow w_t - \eta_w (\hat{r}_w(X, A) - R(A)) \nabla_w \hat{r}_w(X, A)$$

- Setting the step size can be done with the usual approaches.

Actor-critic method

Definition (Actor-critic method, [SB18, p. 321])

Methods that learn approximations to both policy and value functions are often called **actor-critic** methods, where **actor** is a reference to the learned policy, and **critic** is a reference to the learned value function.

- Initialize θ_1 and w_1 (learning rates η_θ and η_w).
- For each round t :
 - Observe X_t , choose action $A_t \sim \pi_{\theta_t}(a | X_t)$, receive $R_t(A_t)$.
 - **[Update actor]** $\theta_{t+1} \leftarrow \theta_t + \eta_\theta \left[\sum_{a=1}^k \nabla_\theta [\pi_\theta(a | X_t)] \hat{r}_{w_t}(X_t, a) \right]$
 - **[Update critic]** $w_{t+1} \leftarrow w_t - \eta_w (\hat{r}_w(X_t, A_t) - R_t(A_t)) \nabla_w \hat{r}_w(X_t, A_t)$

A **slow** direct method: we're slowly adjusting our policy towards larger [estimated] value.

Compare to policy gradient

- The estimate of $\nabla_{\theta} \mathbb{E}[R(A)]$ in policy gradient is

$$(R_t(A_t) - B_t) \nabla_{\theta} \log \pi_{\theta_t}(A_t | X_t).$$

- It's unbiased, but it has variance coming from R_t , A_t , and X_t .
- The actor-critic estimate of $\nabla_{\theta} \mathbb{E}[R(A)]$ is

$$\sum_{a=1}^k \nabla_{\theta} [\pi_{\theta}(a | X_t)] \hat{r}(X_t, a).$$

- Variance comes from X_t and from \hat{r} , but the variance of \hat{r} decreases as we get more data.
- The actor-critic estimate is **biased** by \hat{r} , in general, but we expect it to have **less variance**.

References

- In this module and the previous module, we present approaches to the online contextual bandit problem. The policy gradient and actor-critic methods are usually presented in more general setting of reinforcement learning. The standard textbook reference is [SB18, Ch 13] and [Wil92] is the original paper for “REINFORCE”, which is policy gradient in the reinforcement learning setting.
- In [GBB04] they approach the “optimal baseline” problem in a more general setting, but they define optimality in terms of the trace of the covariance matrix of the gradient estimate. The same approach is taken in [WRD⁺18, Appendix A].
- One can find something similar to our “optimal” baseline approach (with a different baseline for each component of the gradient estimate) in [PS08, Sec 3.2], though they’re in the full reinforcement learning setting.

- [GBB04] Evan Greensmith, Peter L. Bartlett, and Jonathan Baxter, *Variance reduction techniques for gradient estimates in reinforcement learning*, J. Mach. Learn. Res. **5** (2004), 1471–1530.
- [PS08] Jan Peters and Stefan Schaal, *Reinforcement learning of motor skills with policy gradients*, Neural Networks **21** (2008), no. 4, 682–697.
- [SB18] Richard S. Sutton and Andrew G. Barto, *Reinforcement learning: An introduction*, A Bradford Book, Cambridge, MA, USA, 2018.
- [Wil92] Ronald J. Williams, *Simple statistical gradient-following algorithms for connectionist reinforcement learning*, Machine Learning **8** (1992), no. 3-4, 229–256.

- [WRD⁺18] Cathy Wu, Aravind Rajeswaran, Yan Duan, Vikash Kumar, Alexandre M. Bayen, Sham M. Kakade, Igor Mordatch, and Pieter Abbeel, *Variance reduction for policy gradient with action-dependent factorized baselines*, 6th International Conference on Learning Representations, ICLR 2018, Vancouver, BC, Canada, April 30 - May 3, 2018, Conference Track Proceedings, OpenReview.net, 2018.