Explaining Deep Reinforcement Learning Agents In The Atari Domain through a Surrogate Model

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Abstract

One major barrier to applications of deep Reinforcement Learning (RL) both inside and outside of games is the lack of explainability. In this paper, we describe a lightweight and effective method to derive explanations for deep RL agents, which we evaluate in the Atari domain. Our method relies on a transformation of the pixel-based input of the RL agent to an interpretable, percept-like input representation. We then train a surrogate model, which is itself interpretable, to replicate the behavior of the target, deep RL agent. Our experiments demonstrate that we can learn an effective surrogate that accurately approximates the underlying decision making of a target agent on a suite of Atari games.

Introduction

In the field of reinforcement learning (RL), there have been recent strides in domains thought to be previously intractable, such as playing Atari games (Mnih et al. 2013). However, these agents are largely uninterpretable and opaque (commonly referred to as black boxes (Guidotti et al. 2018)). With the right to explain imposed by GDPR (EUd 2018), real world applications of RL could be hampered as there is no consistent way to derive accurate, interpretable explanations for RL agent actions. This is of particular interest in applied fields such as the medical (Holzinger et al. 2017) and judicial (Rudin and Ustun 2018) domains, where a model would need to provide regular explanations comprehensible to a layperson.

There have been prior methods developed to derive explanations in computer vision applications. For example, saliency maps, where pixels important to a model's decision are highlighted and displayed to the user (Simonyan, Vedaldi, and Zisserman 2013), and t-SNE (Maaten and Hinton 2008), that visualizes images that seem similar to the current image according to the model. These approaches highlight important features in making a decision, but are derived from uninterpretable models and do not explain a model's decision making. Model agnostic methods exist (Ribeiro, Singh, and Guestrin 2016), such as SHAP (Lundberg and Lee 2016), which describes the impact each individual feature makes on the deviation of the given prediction from the mean prediction. However, they rely on the feature set itself being interpretable, which is untrue with models that utilize raw pixels as input. If we had an accurate, interpretable model with an appropriate feature set there would be benefits further outside of offering explanations to laypeople. For example, an expert could develop a mental model of the decision making of the agent, driving improvements in the algorithm that created the agent (Hayes and Shah 2017).

In this paper, we show that a simple, but surprisingly accurate explainable model can be learned that approximates the decision making of a deep reinforcement learning agent in the Atari domain. Our approach depends on a state transformation of the raw pixel input to a symbolic, interpretable representation. We demonstrate the proposed state transformation leads to an equivalent representation via proving it is a bijection of the original state space. Lastly, we show that, on a set of Atari games with simple sprites and animations, the behavior of deep reinforcement learning agents can be captured by a decision tree, an interpretable classifier, trained on this symbolic feature representation. In this way the symbolic surrogate decision tree and deep neural network agent create a neuro-symbolic, interpretable system.

Background

Deep Q Networks (DQN) (Mnih et al. 2013) were the first successful demonstration of reinforcement learning in the Atari domain. A DQN consists of a deep approximator of the Q function (Sutton and Barto 2018), and utilizes the Q-learning algorithm (Watkins and Dayan 1992). A myriad of improvements, such as Double DQN (van Hasselt, Guez, and Silver 2015), Prioritized Experience Replay (Schaul et al. 2015) and the Dueling architecture (Wang et al. 2015) were used in tandem to produce the Rainbow architecture, which combines these improvements in an agent that is much more sample efficient than prior DQN based agents (Hessel et al. 2017). We use Rainbow as our testbed agent.

Explainable AI (XAI) (Molnar 2019; Sado et al. 2020), refers to a class of methods to create human-interpretable explanations of a model's behavior (Ehsan et al. 2017). By understanding how the model makes its decisions, the human can then make informed decisions on how to accommodate or address the behavior of the model. For decision making augmented with models, it is integral that the model is able to communicate its decision making in a human understandable manner, which often means a symbolic feature representation

(Goebel et al. 2018).

Juozapaitis et al. described an XAI approach that incorporates the target RL agent by decomposing the rewards and Q values (Sutton and Barto 2018) into a vector representation, where each reward source is one component in the vector (Juozapaitis et al. 2019). One can then formulate the agent action given a certain state in terms of how the agent makes the tradeoff between different reward sources. In many Atari games, there is usually one main source of reward, and occasionally some large source of reward (such as the UFO in *Space Invaders*). Often, the agent is acting without the presence of that large source of reward, leading to a lack of explanation for some actions utilizing this method. Additionally, this approach does not take into account the state of the environment at all, consequently giving no explanation with respect to the current state. For example, in *Breakout*, we wouldn't be able to explain the action with respect to the paddle (the player controlled entity) and the ball (the main interactable entity), since the only reward source is from hitting blocks. In our work we focus on the game entities present in a given observation, augmented with position and velocity, as building blocks for explanations of the agent.

One intuitive approach would be to learn a structural causal model of the agent and explaining the actions of the agent via counterfactuals. Madumal et al. (Madumal et al. 2019) take this route, and focus on answering why (or why not) an agent decides to take an action given the current state. This approach generates explanations that both satisfied human participants and increased the trust of the human participants with respect to the agent. However, the surrogate tends to be a relatively weak fit for the agent, resulting in less accurate explanations of the agent. This is a problem in mission critical systems, or systems for which an accurate mental model of the agent must be understood by the user, such as self driving cars (Shalev-Shwartz, Shammah, and Shashua 2016). We show our approach to be highly accurate and that the explainable surrogate model captures the underlying decision making of the target RL agent. However, we anticipate that Madumal et al.'s results should generalize to our approach, in terms of our similar explanations increasing user satisfaction and trust.

Saliency maps (Simonyan, Vedaldi, and Zisserman 2013) are widely purported to be a strong way of understanding what portions of an image are responsible for the model output. Since Atari agents use the pixels of the frame as a state representation, it seems reasonable to utilize saliency maps in order to explain what influenced an agent in its decision making process. Greydanus et al. (Greydanus et al. 2018) explore the utilization of saliency maps in order to explain to humans what portions of an image an agent utilized in order to make its decisions as a way of garnering trust. However, this approach does not scale to large amounts of data due to the limitation of examining the decision making process of an agent frame by frame, requiring human inspection.

The Surrogate Model

Drawing on (Doshi-Velez and Kim 2017), we define interpretability as the ability to explain or present in understandable terms to a human. The problem we target in this paper is to be able to interpret deep reinforcement learning agents. We focus on the Atari domain (Bellemare et al. 2013), in this initial exploration of our approach, given its popularity as a deep RL domain. We use a surrogate model trained on interpretable features to predict what action the agent will take in a given state. We can then use this interpretable surrogate model to explain the agent, as a proxy for directly explaining the agent. The intuition is that a sufficiently strong surrogate model will capture the agent's decision making with interpretable features, which can then be communicated to a human user.

In order for the surrogate model to be useful for interpretation, we must transform the frame (the raw pixels from an Atari game) into these interpretable features, as utilizing the (x, y) raw pixels as features directly would make meaningful interpretation impossible. One alternative would be to have a human tag each frame with interpretable information, however this would be prohibitively time consuming. We outline a simple and effective automated approach that transforms the raw pixels into a feature set that is both interpretable and rich enough to create a powerful surrogate model. Additionally, we describe the data gathering process for the training dataset of the surrogate model such that it can learn a strong approximation of the decision making process of the agent.

Sprites As Symbolic Features

If one were to ask a human expert for an explanation of their *Breakout* policy, they might answer using the concept of the ball and the paddle. In particular, they might describe their policy in terms of the locations of the ball and paddle, the locations of all of the blocks, and the current velocity of the ball, as these features directly impact the score of the game.

Inspired by this intuition, we chose our interpretable features as the location, velocity, and appearance of game entities. First, we automatically identify the different entities. To do this, we break each frame into groups of pixels to represent each game entity. We refer to these groupings as *sprites* as they represent individual sprites of the game. These sprites have position, and their velocity can be obtained using the changes in sprite position. In contrast to the three dimensional tensor representing the x position, y position and the channel, our feature space consists of the set of sprites, their locations, and their velocities. This allows us to interpret the model utilizing the importance of sprites rather than the importance of pixels.

Transforming Frames Into Features

Given a frame, we need to automatically convert it into the feature space described above. To identify sprites, we need to first identify the background color, to avoid interpreting the background itself as a sprite. We do this by relying on a heuristic of the most common pixel color in a given frame. With the background color identified, we run a depth first search through every unvisited pixel that is not the background color. We consider neighboring pixels to be neighbors in the search space if they have the same pixel color, so that the set of explored frontiers forms a partition over the pixels. In order to increase generalization between similar sprites and to match the feature generation process for Rainbow (Hessel

Algorithm 1: Greedy pixel-wise sprite identification

```
Input: Frame $F \in P$, Neighbor function
  $N : P \to \mathbb{P}(P)$;
Initialise $C : \mathcal{C} \to \mathbb{N}$ such that $C(c) = 0 \forall c \in \mathcal{C}$;
Initialise $V = \emptyset, O = \emptyset$;
for $x, y, c \in F$ do
    $C(c) \leftarrow C(c) + 1$;
end
$B \leftarrow argmax_{c \in \mathcal{C}} C(c)$;
for $p \in F$ do
    $x, y, c \leftarrow p$;
    if $c \equiv B$ or $p \in V$ then
        continue;
    else
        $o \leftarrow DFS(p, V)$;
        $V \leftarrow V \cup o$;
        $O \leftarrow O \cup \{o\}$;
    end
end
return $O$;
```

et al. 2017), this process is run on a downsampled version of the image (downsampled from $(210, 160)$ to $(105, 80)$). In this way we can identify the sprites of the game without human input. See Algorithm 1 for pseudocode of this procedure. We refer to this algorithm as “greedy pixel-wise sprite identification".

Note that we assume that sprites in an Atari game have a uniform pixel color, and the entire sprite is structured so that every pixel in the sprite is adjacent to at least one other pixel in the sprite. As our results demonstrate, this approach is still viable for games where sprites have multiple segments of pixel colors (such as in *Demon Attack*), as each segment of the larger sprite is highly correlated. However, we anticipate that this naive method will need to be extended for domains with a broader palette of potential pixel colors and where individual pixels may have unique colors from all surrounding pixels, such as *DOTA2* or *Starcraft*.

Now that we have the frame grouped into sprites, we need to transform this grouping into features. We designate the lowest and farthest left pixel coordinates of each sprite to be its (x, y) coordinates. If multiple sprites with the same pixels are present, such as multiple aliens in Space Invaders, we sort them by their (x, y) coordinates. Then, for a given sprite returned by this procedure, we have its pixels, x coordinate, y coordinate and its relative position. To find the velocity we treat the data as if it's a time series and take the difference of the data shifted back by one timestep and the current data. See Figure 1 for an example of our representation.

Analysis of Algorithm 1

We provide a proof that our proposed state transformation is a bijection of the raw pixel inputs, to show concretely that the feature space is rich enough to train an accurate surrogate of the agent. Let $P = \mathbb{P}(\mathcal{X} \times \mathcal{Y} \times \mathcal{C})$ represent the set of all possible frames, where $\mathcal{X}$ and $\mathcal{Y}$ are the set of possible x,

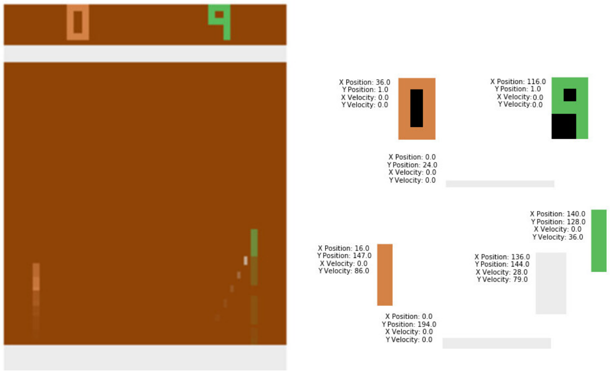

Figure 1: A visual demonstration of the output features after the state transformation for a frame of *Pong*. The left image is the last 5 frames smoothed to show movement, and the sprites and their corresponding features are shown to the right in their relative positions.

y coordinates respectively, $\mathcal{C}$ is the set of all possible RGB colors, and $\mathbb{P}(X)$ is the power set of X. Let $t : P \to Q \subset P$ be the state transformation function.

Proposition. *The state transformation function t separates the argument into a partition. That is, for any frame F, $\cup_{u \in t(F)} u = F$.*

Proof. Let $F \in P$ be arbitrary. From Algorithm 1, we have that for an arbitrary pixel $p \in F$, it must either belong to an object generated by the algorithm or a part of the background. Suppose that $p \in o_0$ and $p \in o_1$, for some $o_0, o_1 \in t(X)$. We then have that p was visited multiple times in Algorithm 1, which violates the loop invariant for the outermost loop. So, we have that for arbitrary $p \in X$, there exists o in $t(X)$ such that $p \in o$. Additionally, suppose that there exists some $p \in F$ such that for all $o \in t(F)$, $p \notin o$. We then have that p must have not been visited in Algorithm 1, which is impossible as we execute the depth first search on every $p \in X$ such that it hasn't been visited previously due to some other $p' \in F$. So, we have that $t(F)$ is a partition of F.

Lemma. *The state transformation function t is a bijection.*

Proof. First, we show that t is an injection. Let $X, Y \in P$ such that $t(X) = t(Y)$. Since $t(X) = t(Y) = O \subset \mathbb{P}(P)$, we have that for all $o \in O$ generated by Algorithm 1, $o \subset X$ and $o \subset Y$. Since $\cup_{p \in o} p \in O$, we have that $X = Y$. Next, we show that t is a surjection. Let O be in the range of t. Since we have that t forms a partition of the argument, we have that $\cup_{o \in O} o = X$ implies that $t(X) = O$. So, we have that t is a bijection.

Obtaining a Surrogate Model For the Agent

Our environment is a Markov decision process $\mathcal{M} = (\mathcal{S}, \mathcal{A}, P, r, \rho_0, \gamma)$ (Sutton and Barto 2018). There are two distinct cases that we would like to examine in our evaluation, in order to encourage diversity in our RL agent's behavior; *noop starts* and *sticky actions alongside noop starts*. For *noop starts*, we modify ρ_0 by executing k noop actions, to diversify the distribution of starting states (Mnih et al. 2015).

For the case with *sticky actions* (Machado et al. 2017), the last selected action is used in place of the agent action with probability $\zeta = 0.25$, as recommended in (Machado et al. 2017), alongside the aforementioned noop starts modification. This gives us more distinct trajectories and forces the agent to learn a more general policy, which we draw on for our evaluation. In order to train a surrogate model, trajectories must be sampled; we employ a sampling procedure for obtaining trajectories corresponding to noop starts $k \rightarrow v$. For each noop start in $[k, k+1, ..., v]$, begin by sampling s_0 from ρ_0. Until termination of the episode, sample a_t according to $\pi(\cdot|s_t)$, and obtain the new state and reward s_{t+1}, r_{t+1}, all while recording the mapping between $t(s_t)$ and a_t. This allows us to divide our trajectories into training and test sets. In the sticky actions case, the state features are augmented with the last action taken in order to expose this information to the surrogate model, which the agent has knowledge of implicitly via the state representation in (Mnih et al. 2013). This gives us a dataset $\mathcal{D}_k$, where k is the amount of noop starts. Once the desired amount of trajectories are obtained, we train a classifier to approximate the mapping of $t(s_t) \rightarrow a_t$, using $\cup_{k \in K} \mathcal{D}_k$, where K is the set of all noop starts used to generate the trajectories. This is reminiscent of imitation learning (Hussein et al. 2017), though in this case we want to approximate the agent's behavior in a symbolic representation, rather than a reward function. In order for the surrogate model to be interpretable, a model of desired interpretable ability should be selected. In particular, a decision tree has strong predictive power (Steinberg and Colla 2009) while still achieving interpretability when trained on interpretable features.

Evaluation

In this section we present an evaluation of our explainable surrogate model in the Atari domain. Specifically, we seek to identify the extent to which our surrogate model is able to successfully learn to approximate the behavior and underlying decision making of a target RL agent.

Implementation Details

In terms of evaluation domain we chose a suite of Atari games, see Table **??** for a list of these games. The first set of these games have simplified sprites and animations, which adhere to the implicit assumptions in Algorithm 1. In particular, the sprites should not have any perspective, and the animation must be either alternating sprites (such as the fish in *Seaquest*) or no animation (such as the ball in *Breakout*). These games should represent ideal evaluation domains for our approach. Additionally, we chose two games with more complicated sprites (*Boxing* and *DemonAttack*), in order to demonstrate how our approach performs when these sprite assumptions are broken.

We choose to use OpenAI Gym (Brockman et al. 2016) for the environment implementations of the Atari games (which uses the Arcade Learning Environment (Bellemare et al. 2013)), and the Stable Baselines (Hill et al. 2018) implementation of Rainbow (Hessel et al. 2017), and frame skip. We examine the cases of noop starts and sticky actions combined with noop starts. We train the Rainbow agent for 1,000,000 timesteps on each game. We used the same parameters as in (Hessel et al. 2017). We limit our noop starts to be [0, 29] inclusive, and for every 4 frames obtained from ALE, we use max(frame 3, frame 4) as an observation. Since Rainbow uses a downsampled version of the pixel observations from the Atari games, we have downsampled the pixel representation provided by the Arcade Learning Environment from $(210, 160)$ to $(105, 80)$, in order to better represent the input that Rainbow is using while still minimising sprite distortion due to downsampling. For our surrogate models, we have chosen a decision tree (Steinberg and Colla 2009) for its performance and high interpretability. We have utilized Scikit-learn (Pedregosa et al. 2011) for a decision tree implementation, using their default hyperparameters, which allows for easy adoption and extension of this work.

We require some method to understand what features are responsible for a given prediction deviating from the mean prediction to compare to our explanations. Shapley values (Shapley 1952) fit this requirement. We can consider the classification problem as a game, with the players as the features. If we assume the fairness axioms described in (Shapley 1952), then we have that the unique solution to a distribution of payout for each player is given by the Shapley value. SHAP (Lundberg and Lee 2016) was created as a way to efficiently estimate Shapley values for individual predictions, and TreeSHAP (Lundberg, Erion, and Lee 2018) gives a method for exactly calculating the Shapley values for tree based models in polynomial time. Thus, TreeSHAP is appropriate to obtain the exact Shapley values for our surrogate model, given we use a decision tree (Steinberg and Colla 2009).

Experiments

We chose to focus on the problem of demonstrating that our interpretable surrogate model accurately reflects the behavior and decision making of the RL agent. This is crucial, as while other approaches have demonstrated that even inaccurate explanations increase user trust (Ehsan et al. 2019; Madumal et al. 2019), an accurate explanation is required for many domains and applications. As such, we designed our experiments to answer the following research questions:

1. Given some agent and environment, can a surrogate model be trained that is highly accurate?
2. Does a surrogate model overfit to the trajectories it was trained on, or can it generalize to trajectories it hasn't been trained on?
3. To what extent does the model capture the underlying decision making of the agent?

In order to answer (1), we obtain 25 sampled trajectories using 0, 1, ..., 24 noop actions at the start of the episode, following the procedure outlined above, with and without sticky actions (Machado et al. 2017) with probability 0.25. We train the surrogate in a supervised fashion, and evaluate both the accuracy and cross entropy using a 5 fold split. The results can be found in Table **??**. This demonstrates that it is possible to learn a very accurate approximation for the agent, at least for interpolation in between trajectories. The usage of

Game	Accuracy (%)	Cross Entropy	Accuracy (%) (Sticky)	Cross Entropy (Sticky)
Atlantis	89.5 ± 0.129	3.32 ± 0.027	81.6 ± 0.209	6.21 ± 0.0740
Gopher	93.51 ± 0.056	2.242 ± 0.019	84.6 ± 0.178	5.31 ± 0.0580
Breakout	92.285 ± 0.283	2.66 ± 0.097	85.6 ± 0.358	4.93 ± 0.122
Star Gunner	87.477 ± 0.309	4.223 ± 0.118	73.9 ± 0.345	9.02 ± 0.119
Pong	90.271 ± 0.027	3.306 ± 0.011	82.369 ± 0.169	6.076 ± 0.058
Qbert	97.525 ± 0.132	0.524 ± 0.025	91.8 ± 0.327	2.83 ± 0.117
Space Invaders	78.94 ± 0.404	7.047 ± 0.128	78.0 ± 0.260	7.50 ± 0.0930
Seaquest	93.2 ± 0.234	0.675 ± 0.239	66.2 ± 0.120	11.7 ± 0.0420
Ms Pacman	97.977 ± 0.087	0.47 ± 0.03	88.7 ± 0.199	3.79 ± 0.0610
Kung Fu Master	98.677 ± 0.085	0.373 ± 0.035	88.1 ± 0.125	4.10 ± 0.0410
Asterix	95.7 ± 0.190	0.137 ± 0.007	91.2 ± 0.362	2.85 ± 0.124
Demon Attack	87.692 ± 0.163	4.251 ± 0.056	79.6 ± 0.237	7.03 ± 0.082
Boxing	74.11 ± 0.169	8.872 ± 0.058	77.6 ± 0.249	7.73 ± 0.0870

Table 1: Surrogate model accuracy and cross entropy. A line separates those games that match our sprite assumptions and those that do not.

sticky actions causes much more variance in the trajectories (Machado et al. 2017), causing greater diversity in the training data, likely being the cause of the performance reduction. However, even in the sticky actions case, the resulting surrogate models are still very powerful despite being simple decision trees. We also note that for games like *Boxing*, where the sprite animation is complicated due to the moving hand creating a variety of different sprites, there is a huge amount of sparsity in the data for a given state. However, despite this complexity and the fact that Boxing violated our sprite assumptions, the resulting surrogate model is still better than random chance.

Now, the next question is if this surrogate model can generalize to trajectories that it has never seen before. This is equivalent to answering (2). We consider this problem solely in the domain of noop starts, without loss of generality. Note that the agent attempts to maximize its return over trajectories where the starting state is sampled from choosing 0, 2, ..., 29 noop starts. We have trained the model on the trajectories using 0, 2, ..., 24 noop starts, leaving the trajectories generated by 25, 26, ..., 29 noop starts as a test set. As such, we obtain the 5 trajectories aforementioned, using the method outlined in section 3.2. We then use this dataset as a test set for the surrogate model. The results can be found in Table **??**. We see that the performance of the surrogate model is still strong, in some cases stronger than in the training set. This indicates that the model has learned a good, general model of the behavior of the agent. The consistently strong accuracy results also stand out in comparison to other XAI approaches (Madumal et al. 2019; Ehsan et al. 2019). There is a significant degradation in performance over the unseen trajectories for *Boxing*, likely due to the lack of features that describe objects relative to one another in the feature space, greatly restricting the ability for the model to learn location invariant features. Said features appear to be important to the policy learned for the non-sticky action case.

Our third research question asks whether or not the learned decision making of the model accurately approximates the underlying decision making of the agent. This is important, as it's possible our surrogate model is getting the right answer for the wrong reason, or a type III error. But we cannot directly compare the decision making as that would require matching decision nodes and neural network weights. However, if it is the case that the surrogate model has accurately approximated the Rl agent's policy in symbolic features, than these symbolic features should be integral to the RL agent's policy. As such, we show that a permutation of the symbolic features important to the surrogate model's decision making also results in a significant change in agent behavior.

We use the surrogate model to produce adversarial examples (Goodfellow, Shlens, and Szegedy 2014). Instead of a single decision tree, we employ a tree ensemble (LightGBM (Ke et al. 2017) with default hyperparameters) to allow for many possible candidate splits to search through in order to generate said adversarial examples. We use the degree of change in the prediction of the surrogate model as a metric for producing adversarial examples, as such a single decision tree would be insufficient. To begin with, we take all sprites in the state, and rank them according to the maximal Shapley value of each of their features for a decision tree's predicted action. We then consider the sprites in the top 10% of this list. For each decision tree in our surrogate model, we do a 3-ply search over the splits, obtaining eight different subsets of the dataset. We sample one state from each subset. For each sampled state, we swap the feature values corresponding to the top 10% of sprites with the feature values in the sampled state. This gives us 800 possible adversarial examples, as we employ a surrogate model of 100 decision trees. We take the example which minimizes the original prediction of the surrogate model to be our adversarial example. This is essentially the permutation of the original state that most changed the predicted behavior from our surrogate model. At no point do we query the deep RL agent when producing these adversarial examples. If the agent is using the same features in its decision making, it follows that it's behavior should change when the surrogate model's prediction changes.

We collected 200 (state, action) pair permutations from the trajectory with 24 noop starts, and considered only the

Game	Accuracy (%)	Cross Entropy	Accuracy (%) (Sticky)	Cross Entropy (Sticky)
Atlantis	96.2 ± 0.791	0.272 ± 0.0252	90.03 ± 7.08	3.29 ± 2.45
Gopher	98.1 ± 0.115	0.205 ± 0.0159	83.4 ± 0.952	5.71 ± 0.338
Breakout	98.2 ± 0.537	0.158 ± 0.00567	96.33 ± 2.04	1.27 ± 0.705
Star Gunner	95.0 ± 0.971	0.150 ± 0.0207	82.4 ± 6.64	6.02 ± 2.29
Pong	90.0 ± 0.372	0.330 ± 0.00671	83.6 ± 0.709	5.64 ± 0.240
Qbert	99.1 ± 0.319	0.0282 ± 0.00505	97.19 ± 1.29	0.703 ± 0.481
Space Invaders	99.5 ± 0.00265	0.118 ± 0.0125	65.3 ± 5.34	11.7 ± 1.88
Seaquest	99.0 ± 0.185	0.121 ± 0.00815	72.6 ± 4.06	9.47 ± 1.40
Ms Pacman	97.4 ± 0.00694	0.0620 ± 0.00909	98.5 ± 0.443	0.121 ± 0.023
Kung Fu Master	99.9 ± 0.0361	0.324 ± 0.00345	85.5 ± 1.74	4.93 ± 0.581
Asterix	95.7 ± 0.19	0.137 ± 0.007	66.9 ± 6.86	10.9 ± 2.33
Demon Attack	67.8 ± 6.38	0.964 ± 0.139	64.6 ± 2.13	12.2 ± 0.737
Boxing	58.0 ± 2.33	1.33 ± 0.08356	76.2 ± 0.547	8.20 ± 0.189

Table 2: Surrogate model accuracy and cross entropy on unseen trajectories.

Game	Agent action changed %
Atlantis	54.8
Gopher	46.8
Breakout	92.5
Star Gunner	69.2
Pong	92.8
Qbert	74.1
Space Invaders	70.0
Seaquest	76.8
Ms Pacman	94.6
Kung Fu Master	73.6
Asterix	40.6
Demon Attack	62.7
Boxing	86.0

Table 3: Probability of agent changing action given permuted state.

(state, action) pairs. The results in terms of the percentage of instances where the agent changed its action from the original compared to the permuted state can be found in Table **??**.

We can see that in general, our adversarial examples cause the agent to change its predicted action, with an average probability of 72% across all games. Due to the nature of these comparisons, we consider them similar to correlation, which would imply a strong average alignment in decision making between the surrogate and agent. This is surprising given how much smaller and simpler our surrogate is compared to Rainbow, even in the case of using a random forest in comparison to a single decision tree. The alignment remained strong in the more complex games where our surrogate's action prediction accuracy was lower. This indicates that even in the more complex games our surrogate is still identifying the important features on which the agent makes its decisions. We do not anticipate that this was due to the use of a random forest instead of a single decision tree, as the decision tree performed roughly equivalently to the random forest across the first two evaluations in our experiments. We note that Rainbow is a limiting factor here, as we cannot measure the confidence change in the action, which would give us a more nuanced measure of impact.

We have shown thus far that the model is a strong surrogate of the agent, both for interpolation of trajectories previously seen and on trajectories not explicitly seen before, and that the decision making of both the agent and model is well-aligned. However, this does not necessarily mean that the features learned by the surrogate model also match human intuition. In Figure 2 we visualize the sprites with the highest Shapley values in the selected frames for two of the Atari games. We can see that the player sprite, along with the sprites the player would interact with impacts the deviation of the given predicted action distribution from the mean predicted action distribution, with little regard to other objects of the scene. This agrees with our intuition for these games, in terms of which sprites are of most importance. Additionally, in figure 3, we visualize the first three levels of the decision tree obtained from *Breakout*, all of which focus on paddle orientation. There is a huge emphasis on paddle orientation and velocity that agrees with human intuition, such as continuing to move left when already moving left, and likewise with moving right. Additionally, opting to do noops after coming in contact with the ball is a common strategy observed with Breakout agents trained by DQN, which is emphasized by the Paddle X position node. One oddity is that the ball touching the paddle is recognized as a unique sprite compared to the ball or paddle individually. This is due to the simple sprite finding technique utilized, and the fact that both ball and paddle are the same color. However, represented visually, and with some knowledge of *Breakout*, the sprite still reads clearly.

Limitations and Future Work

We note a number of limitations and corresponding areas of future work. From the results with *Demon Attack* and *Boxing*, we can identify that our approach at times underperforms in more complex games. We anticipate that this is partially due to our naive sprite detection approach. In future work we plan to draw on techniques like Blob Detection (Danker and

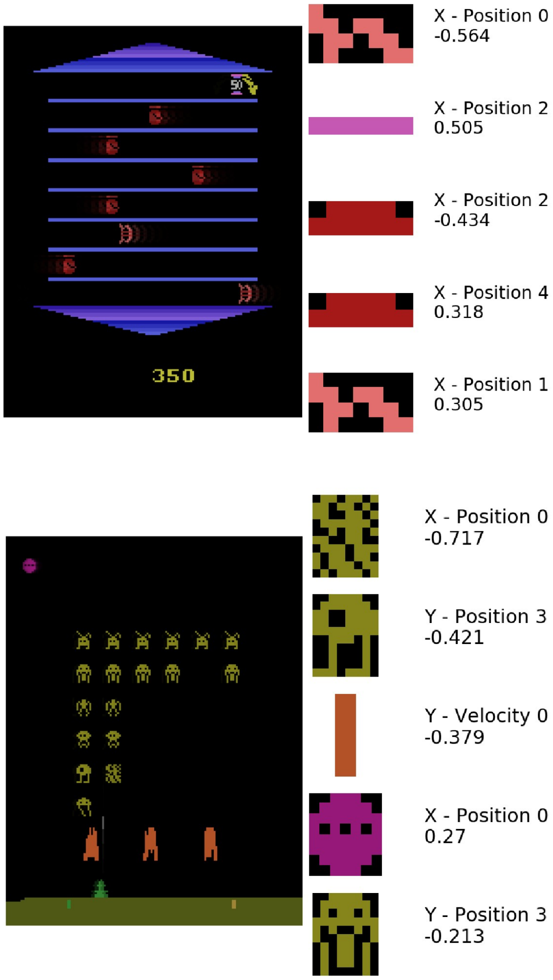

Figure 2: A pictorial representation of the highest absolute Shapley values given a specific game state. The left frame occurs 1 time step before the right frame. The 5 sprites on the right are ordered by their Shapley value, and additional information (which coordinate, position or velocity, and which sprite (ordered from top left to bottom right)).

Rosenfeld 1981) and image segmentation (Felzenszwalb and Huttenlocher 2004) to address this.

Atari is a relatively simple domain. While this is appropriate for an initial exploration of this approach, given it's popularity for deep RL research, it is far less complex than many real world domains. While we drew upon intuitions unique to video games in this work, these assumptions will not hold in other domains. We anticipate that these other domains, particularly those reliant on natural language, will require their own non-trivial state transformations.

We do not include a human subject study, instead focusing this paper on demonstrating that our method shows strong accuracy with regards to an RL agent compared to prior work (Madumal et al. 2019; Ehsan et al. 2019). In particular, interpretability, as discussed in this paper, relies on the intrinsic interpretability of decision trees and Shapley values. It's uncertain whether or not these decision trees are practically interpretable with human subjects, which will be explored in further work or how they might be employed to produce explanations for those without technical knowledge. We intend to delve into the specific impact of our surrogate model on human experience in future work.

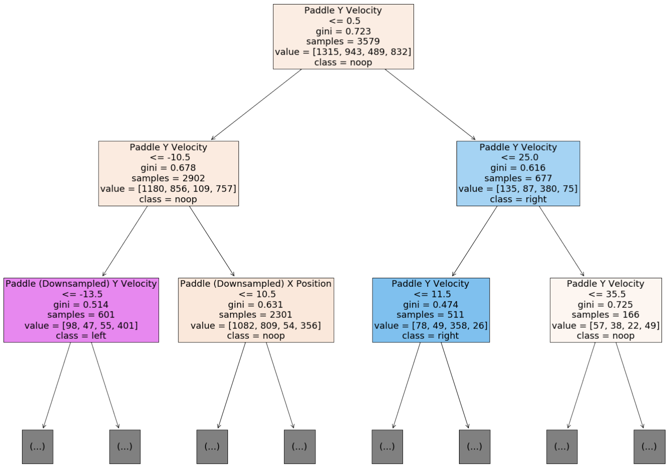

Figure 3: A visualization of the first 3 levels of the decision tree classifier learned on the training data from Breakout. The colors correspond to the chosen label; tan corresponds to class 0 (noop), blue corresponds to class 2 (move right) and pink corresponds to class 3 (move left).

Conclusion

In this paper, we have presented a simple, yet surprisingly effective approach to train an accurate surrogate model. We proved that our interpretable representation is a bijection of the original state space. Through experimentation we demonstrated that the surrogate model learned to accurately approximate the behavior of Rainbow on a set of Atari games. This indicates that the approach is an appropriate one to add interpretability to complex, black box agents in simple domains.

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Ethics Statement

We introduce an Explainable AI approach, which has the potential to offer broad impacts in terms of how and where Reinforcement Learning can be applied. Our approach is simple, but surprisingly powerful. This is beneficial, as it indicates it will be easier for others to adapt this approach to their needs. However, because our approach only demonstrated strong performance on simple domains, there is the potential for negative impact if it is brought to more complex domains too soon. Without sufficient improvement, our approach applied to a complex RL agent may present inaccurate explanations that still increase user satisfaction and trust (Madumal et al. 2019). This could be devastating in high-risk scenarios, for example doctors trusting faulty diagnoses (Holzinger et al. 2017). We therefore highly caution against applying this approach broadly until it has been improved to function in more complex domains and suitable research into its impact on users has been completed.

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