

# Brick-by-Brick: Combinatorial Construction with Deep Reinforcement Learning

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## Introduction

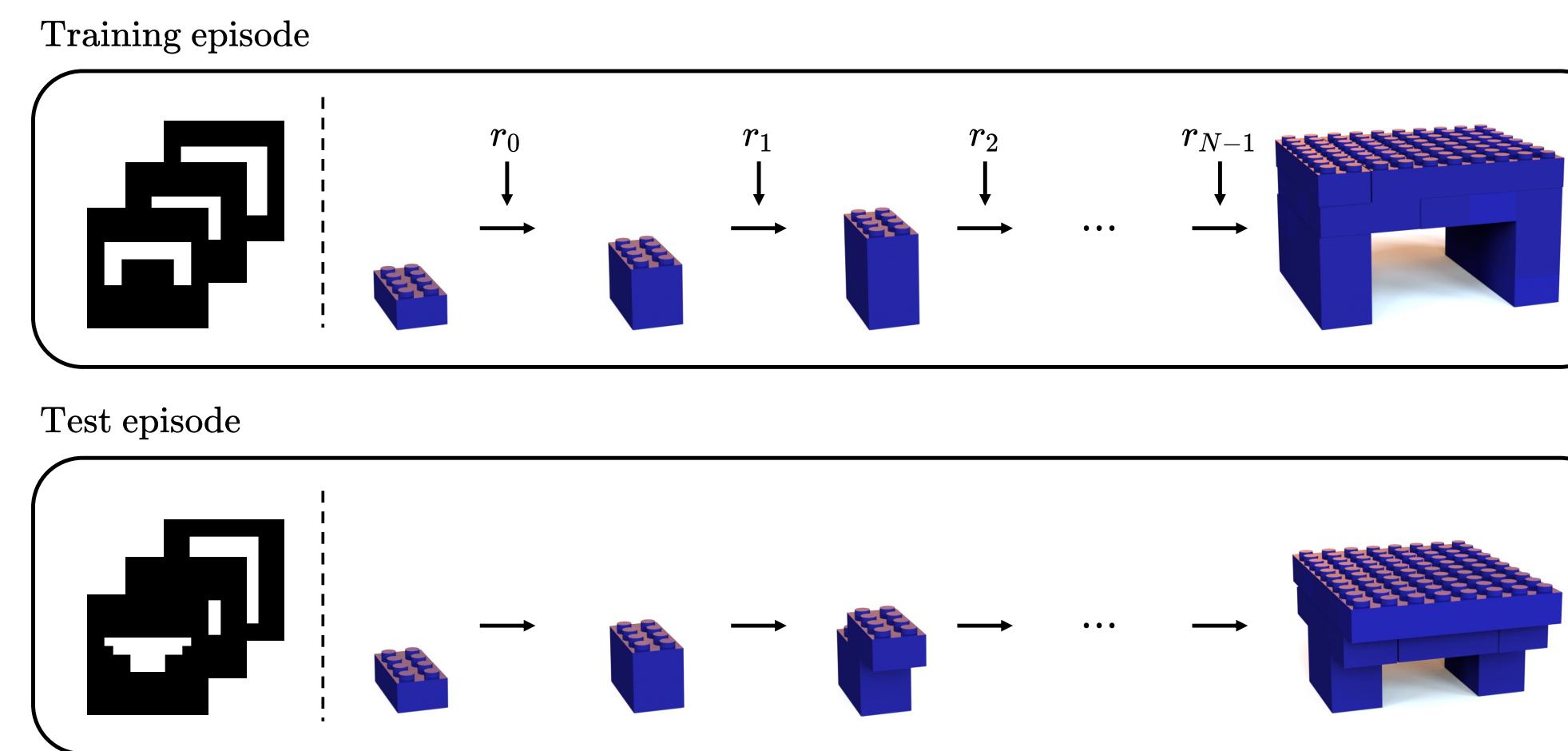
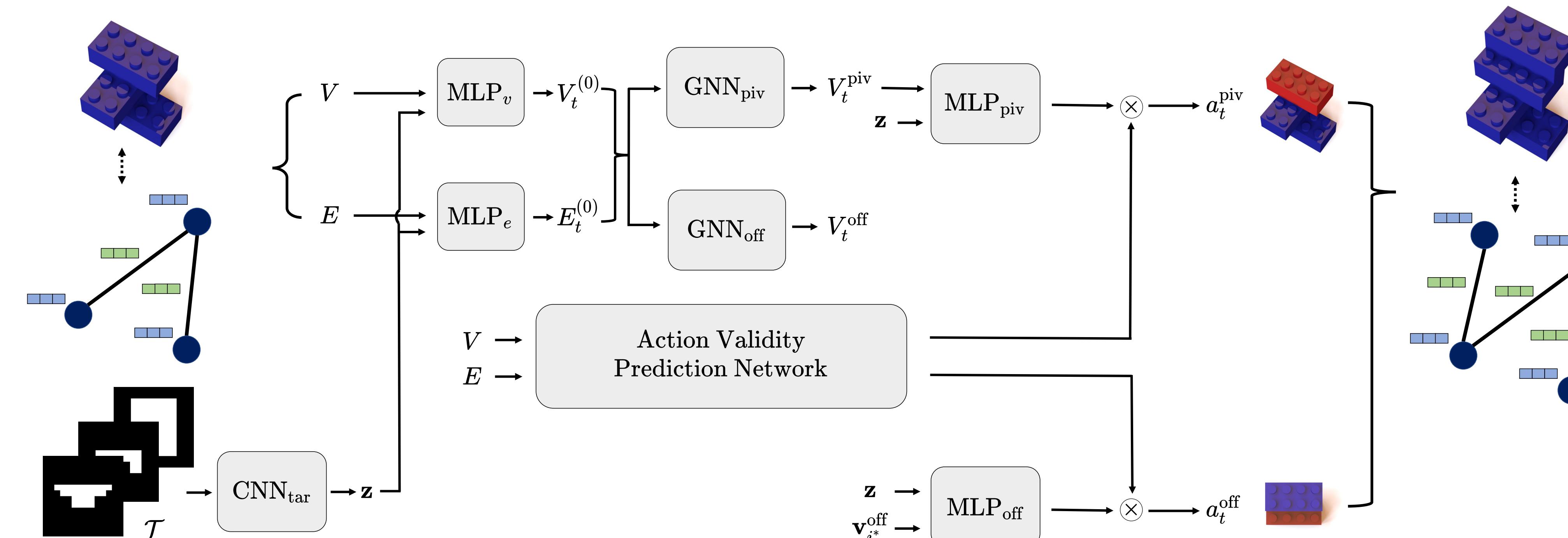
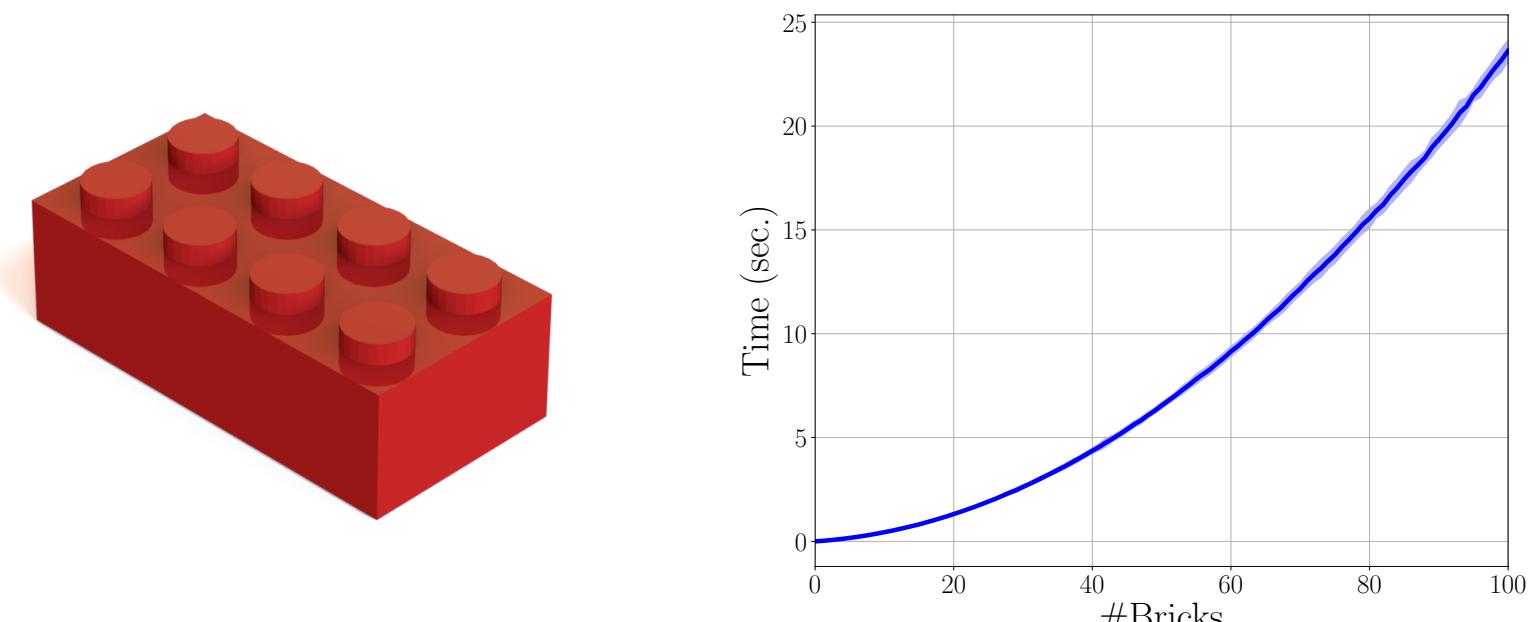


Figure 1: Training and test episodes

- Sequentially assemble unit primitives given incomplete target information, which is an interesting yet challenging problem defined on a combinatorial space.
- Propose an RL approach, which does not require sequence-level supervision.
- Adopt an action validity prediction network to handle both an indefinite action space and the existence of many invalid actions when applying RL.

## Combinatorial Construction

- $2 \times 4$  brick as a unit primitive, which has eight studs and their fit cavities.
- Consistently growing possible positions to assemble a brick.
- For only six  $2 \times 4$  bricks, 915,103,765 possible combinations.



## Action Space

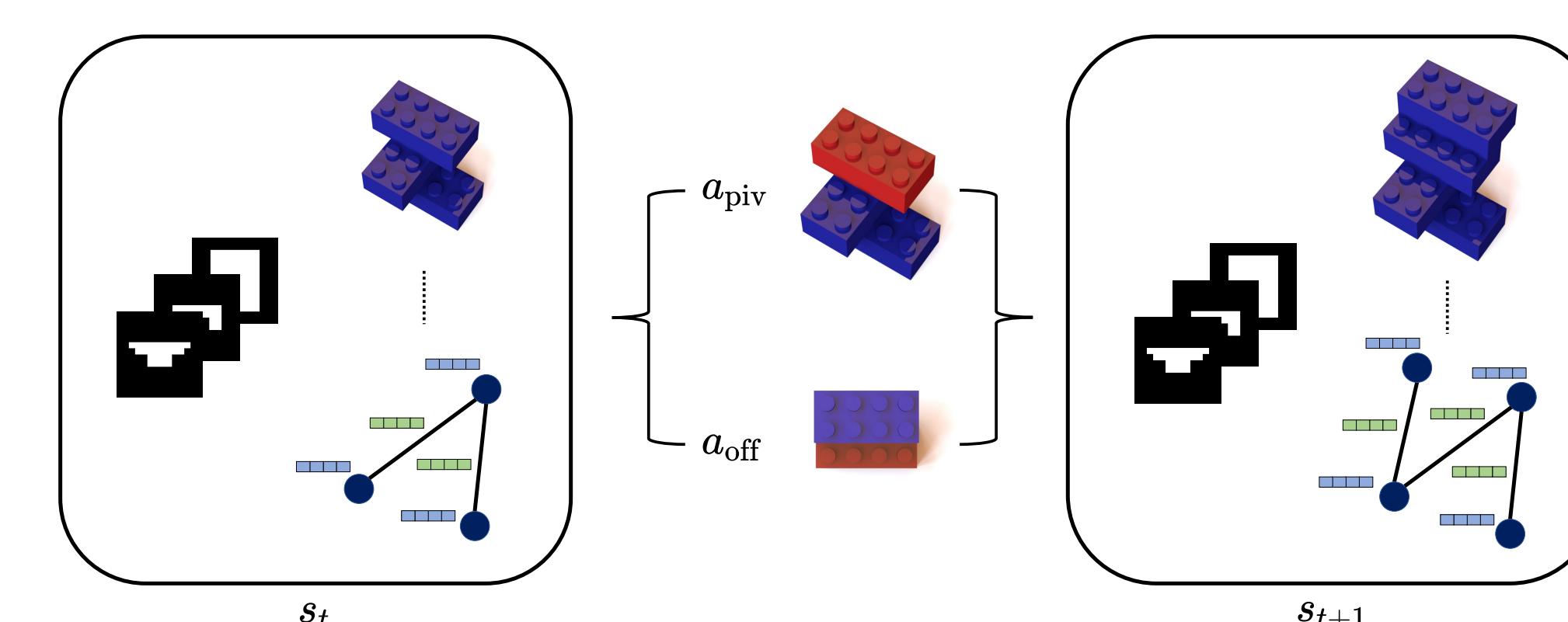


Figure 3: Successive action space

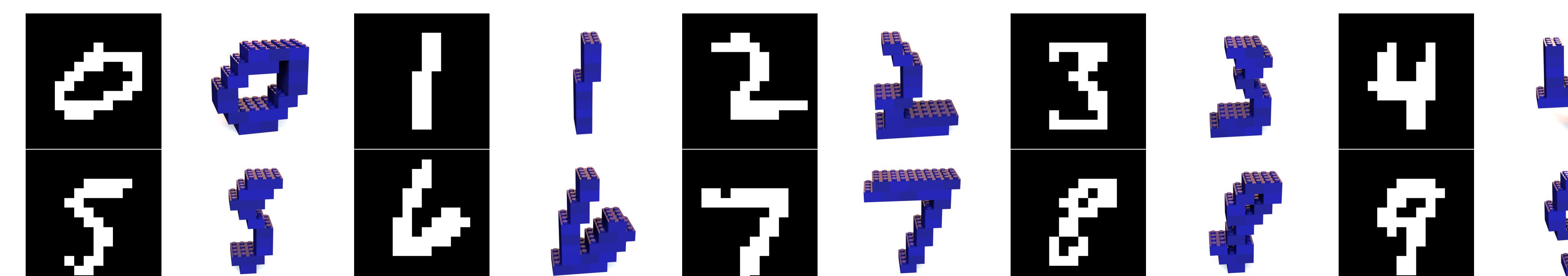


Figure 4: Qualitative results on MNIST construction

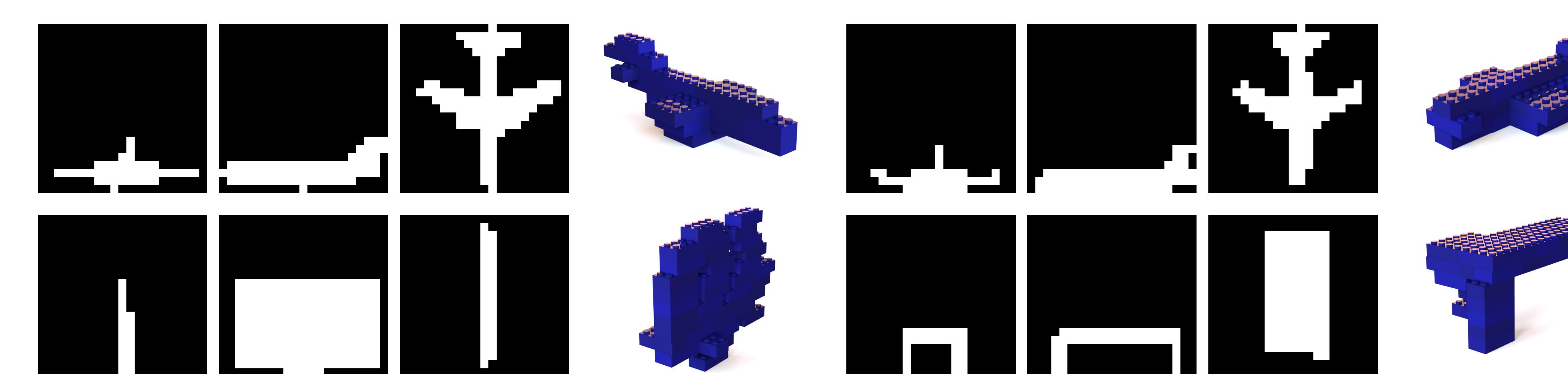


Figure 5: Qualitative results on ModelNet construction

## Brick-by-Brick

- Suppose that target information  $\mathcal{T}$  is given as partial information.
- Represent each  $t$ -th state  $s_t$  of the MDP as a tuple of a directed graph  $G_t$  and target information  $\mathcal{T}$ , i.e.,  $s_t = (G_t, \mathcal{T})$ .
- With  $t$  bricks assembled, define an action  $a_t = (a_t^{piv}, a_t^{off})$ .
- Measure the overlap between the currently-assembled bricks and the target object as a reward function:

$$\Delta\text{IoU}(\mathbf{C}_t, \mathbf{T}) = \frac{\text{vol}(\mathbf{C}_t \cap \mathbf{T})}{\text{vol}(\mathbf{C}_t \cup \mathbf{T})} - \frac{\text{vol}(\mathbf{C}_{t-1} \cap \mathbf{T})}{\text{vol}(\mathbf{C}_{t-1} \cup \mathbf{T})}, \quad (1)$$

where  $\mathbf{C}_t$ ,  $\mathbf{C}_{t-1}$ , and  $\mathbf{T}$  are the occupied voxels at timestep  $t$ , timestep  $t-1$ , and a desired target, respectively.

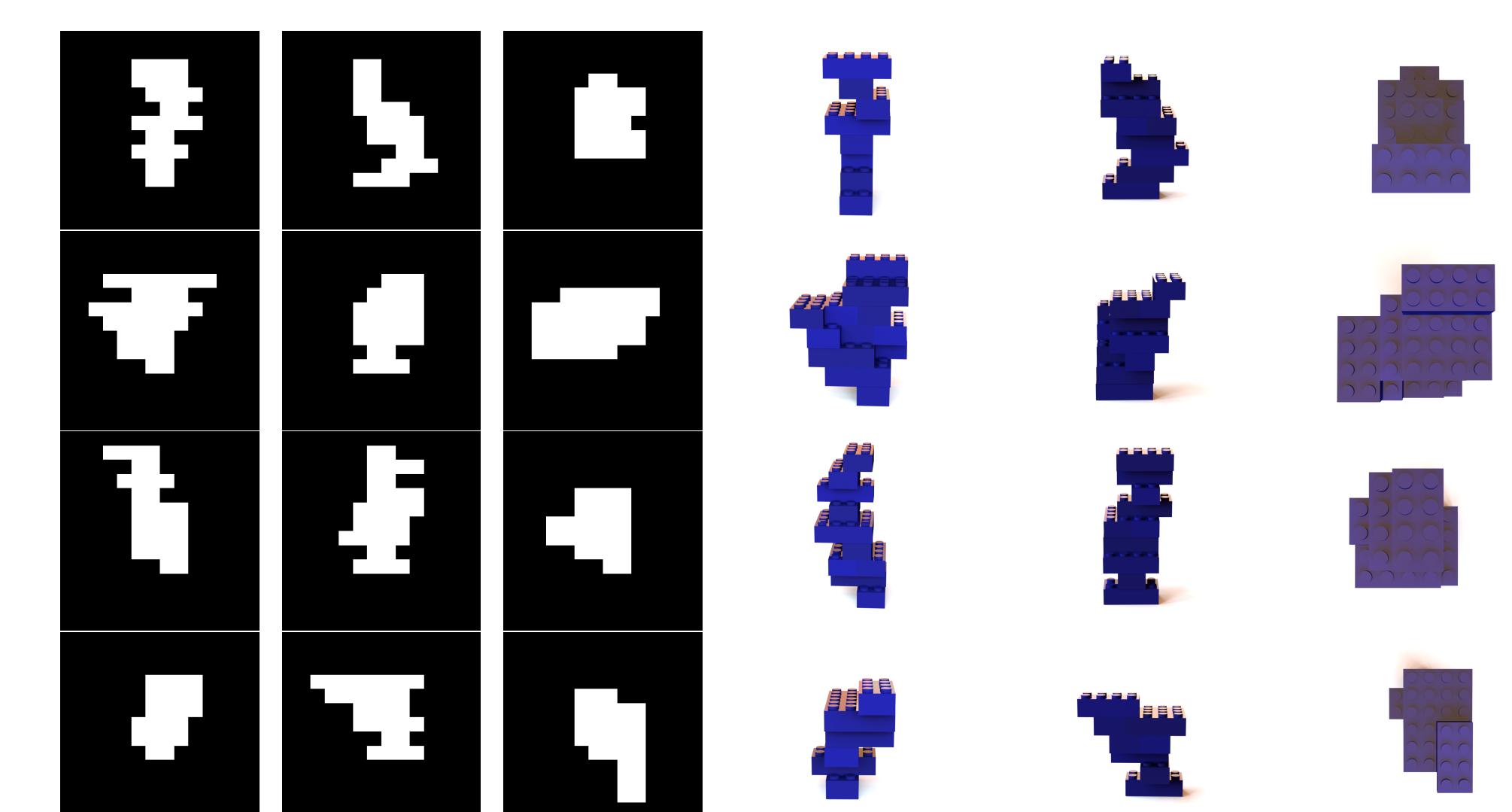


Figure 6: Results on randomly-assembled object construction

## Available on arXiv/GitHub



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