AIFA: Stochastic Planning MDP

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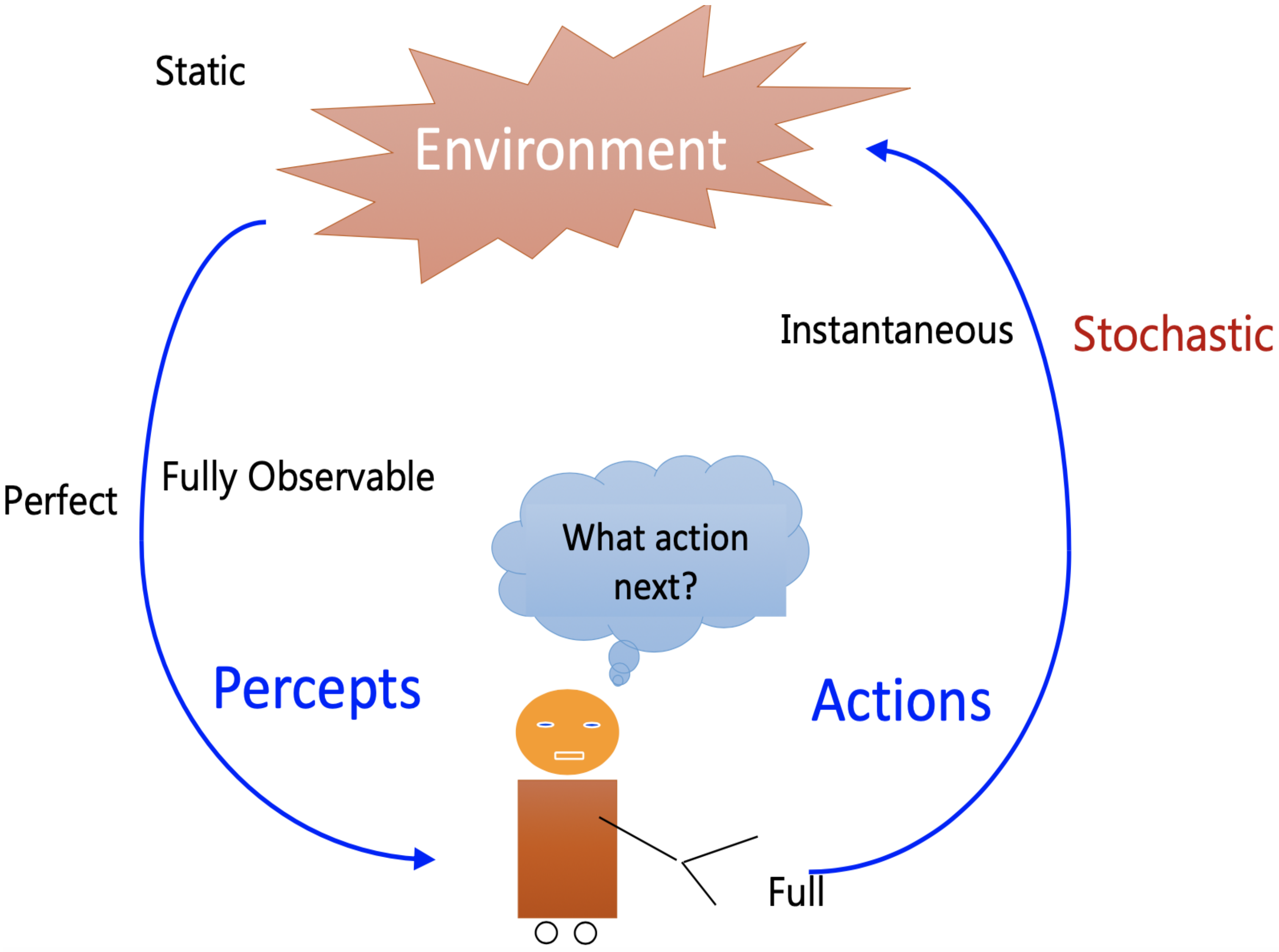
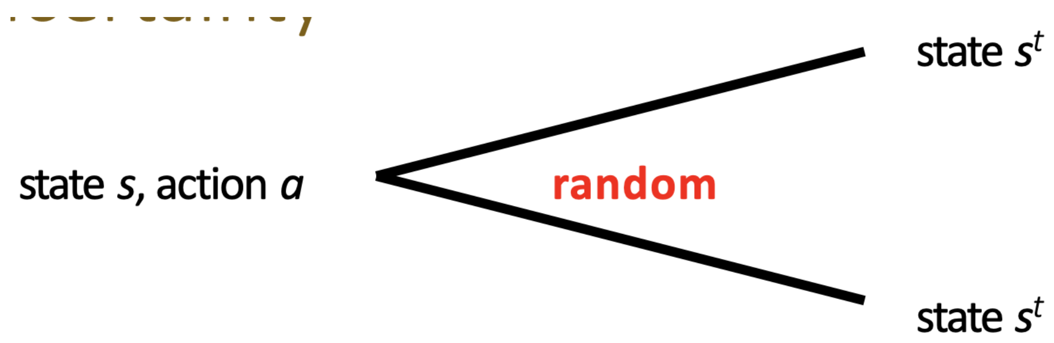
Markov Decision Processes

- Value Iteration
- Policy Iteration

Planning under Uncertainty



Uncertainty



Randomness:

- could be caused by limitations of the sensors and actuators of the robot
- could be caused by market forces or nature

…

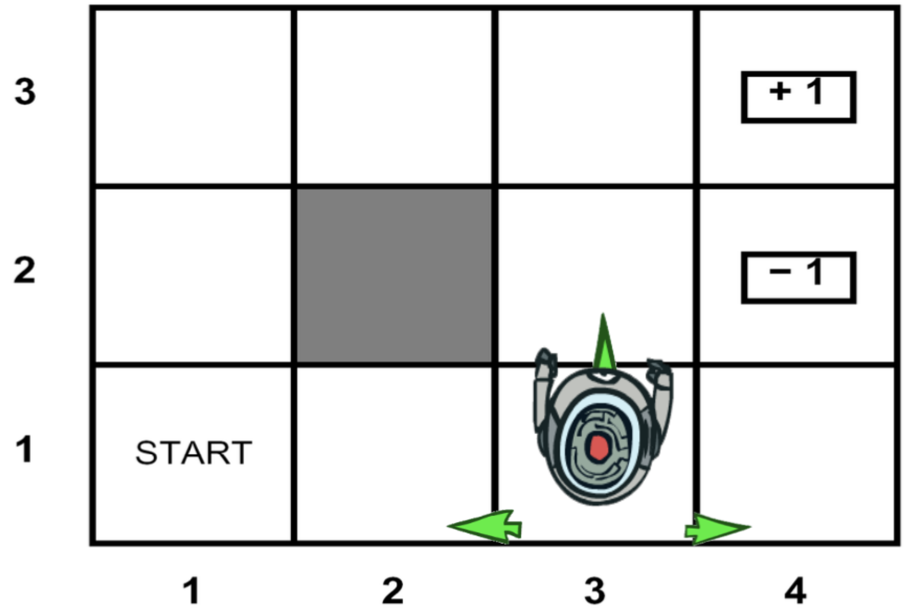
- Robotics: decide where to move, but actuators can fail, hit unseen obstacles, etc.
- Resource allocation: decide what to produce, don’t know the customer demand for various products
- Agriculture: decide what to plant; don’t know weather and thus crop yield

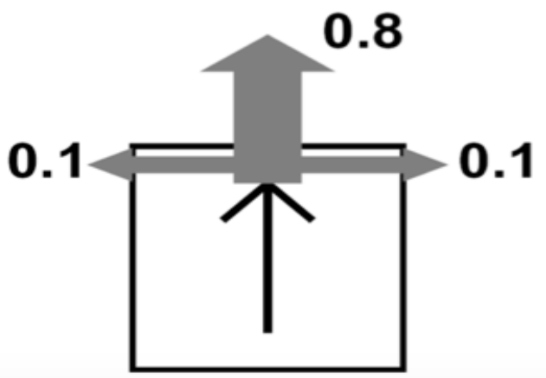
Example: Grid World

- 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
  - Small “living” reward each step
  - Big rewards come at the end

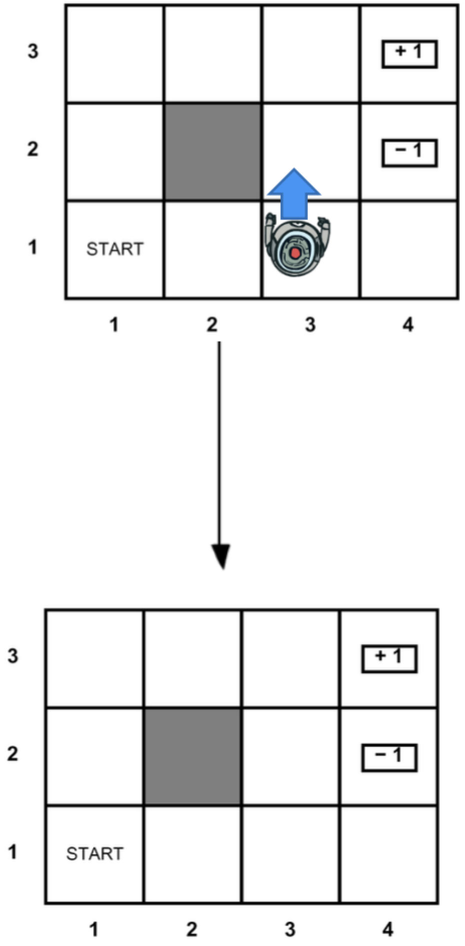
- Goal: maximize sum of rewards



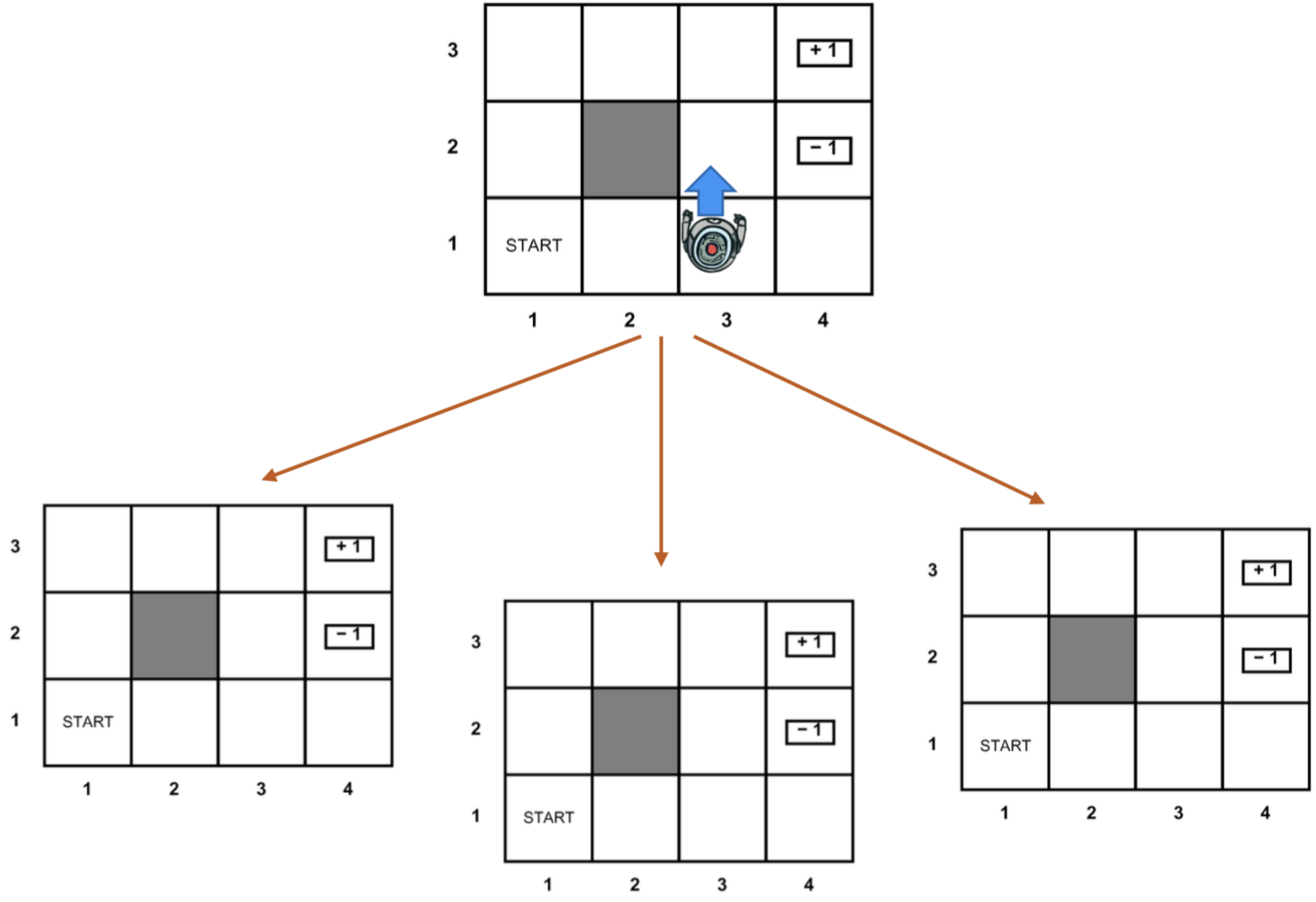


Grid World Actions

Deterministic Grid World

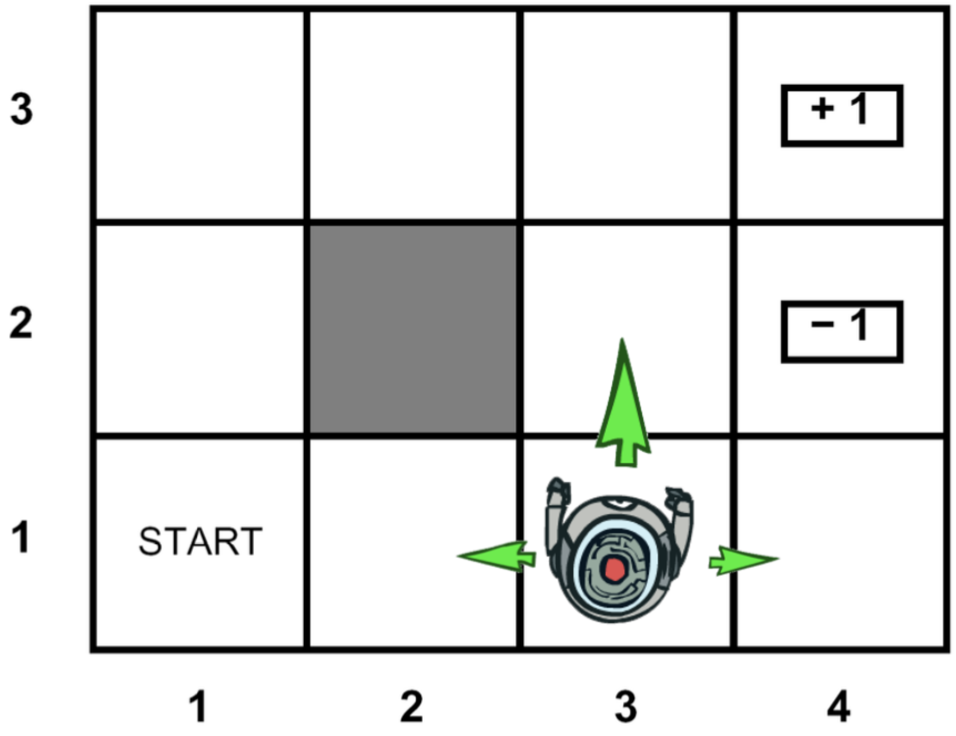


Stochastic Grid World



Markov Decision Process

- 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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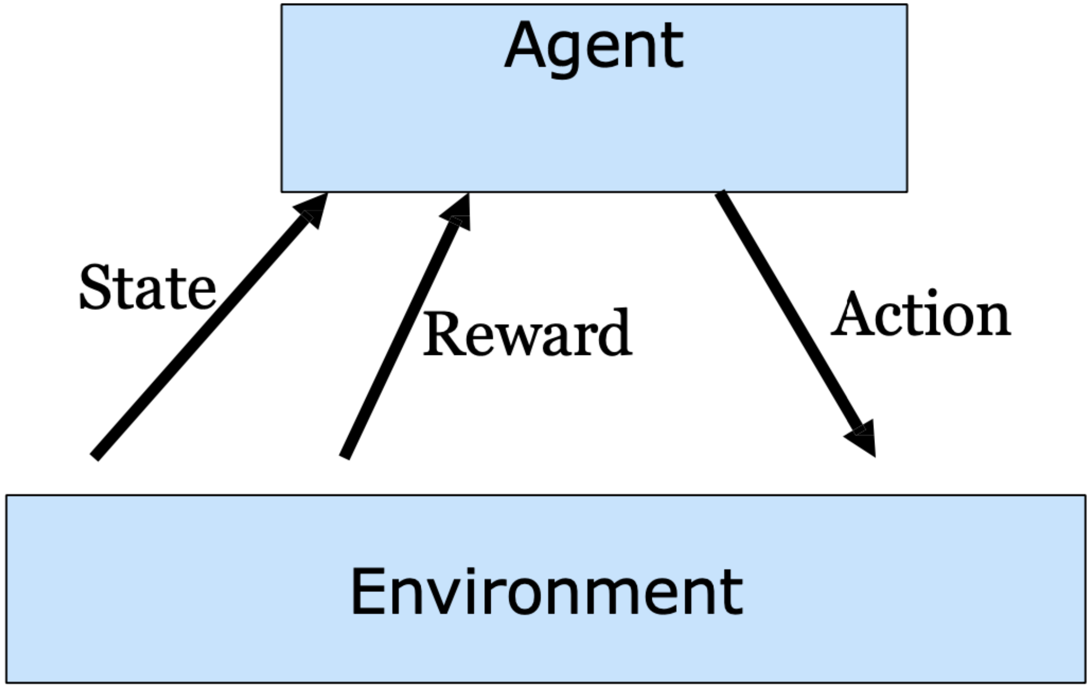
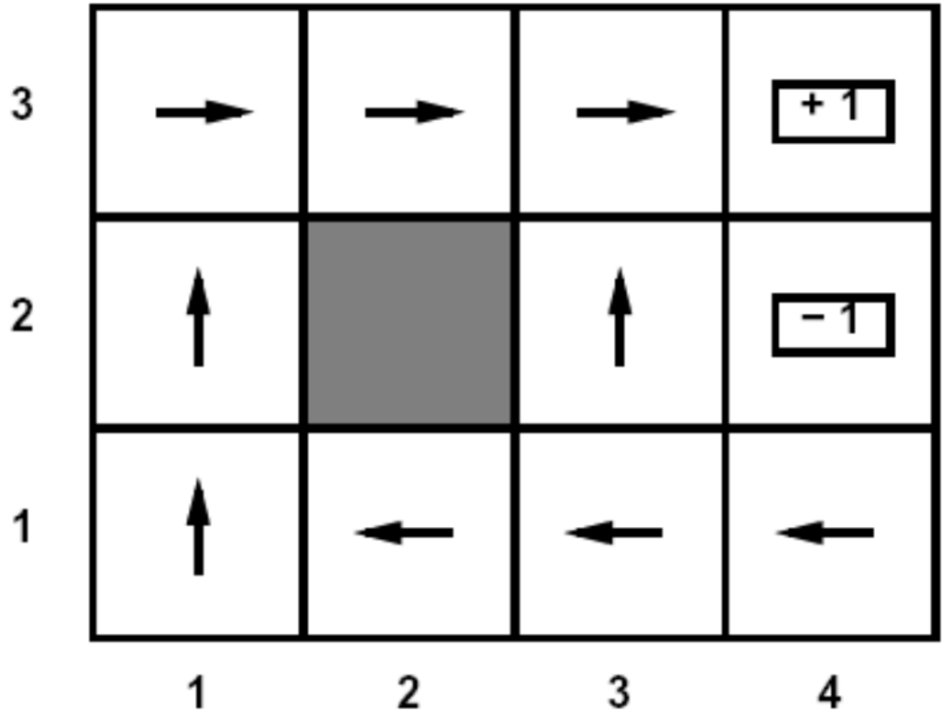


Goal: Learn to choose actions that maximize reward

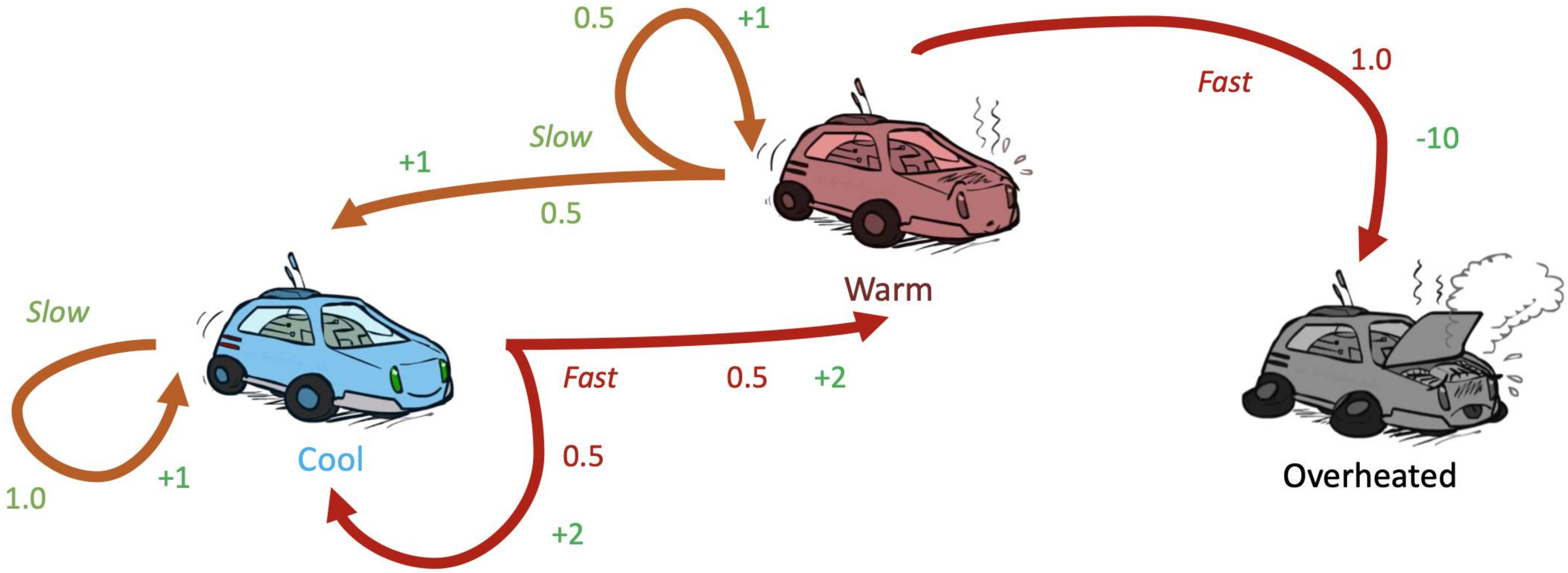
Solution to MDP: Policies

- For MDPs, we want an optimal policy $\pi^*: S \rightarrow A$
- A policy π gives an action for each state
- An optimal policy is one that maximizes expected utility if followed

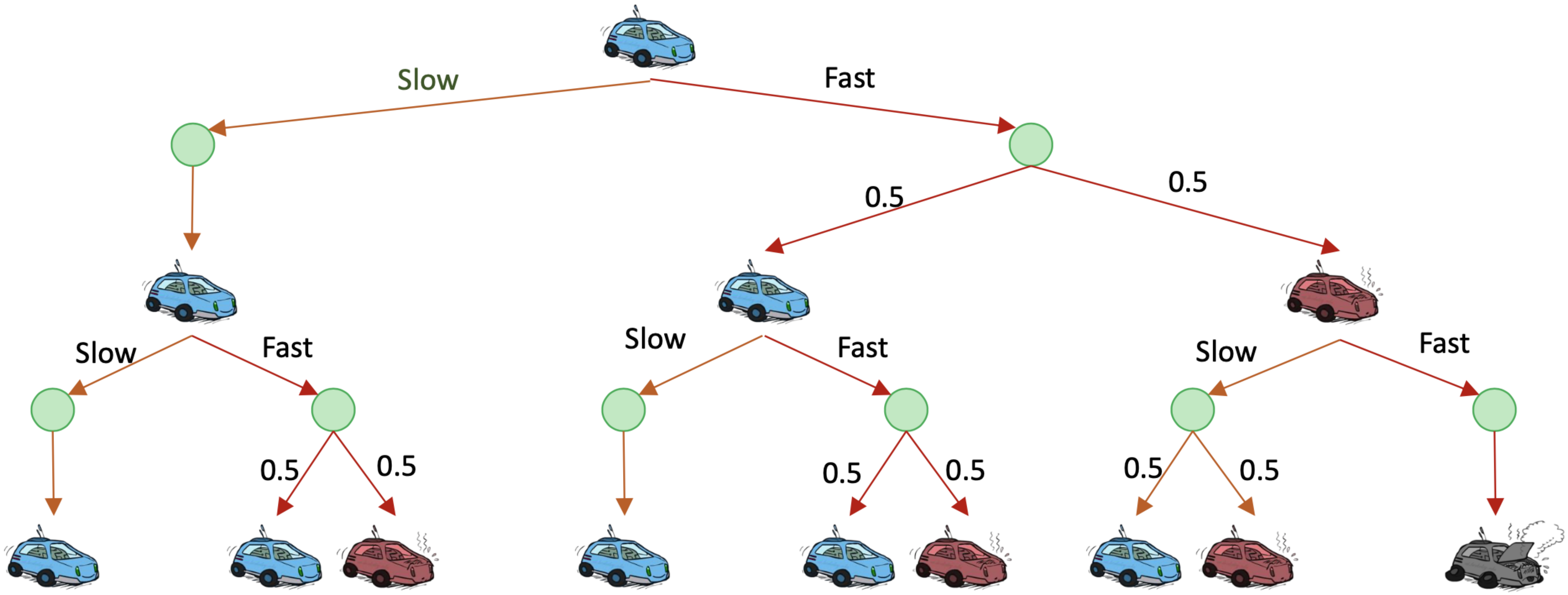


Example: Racing

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

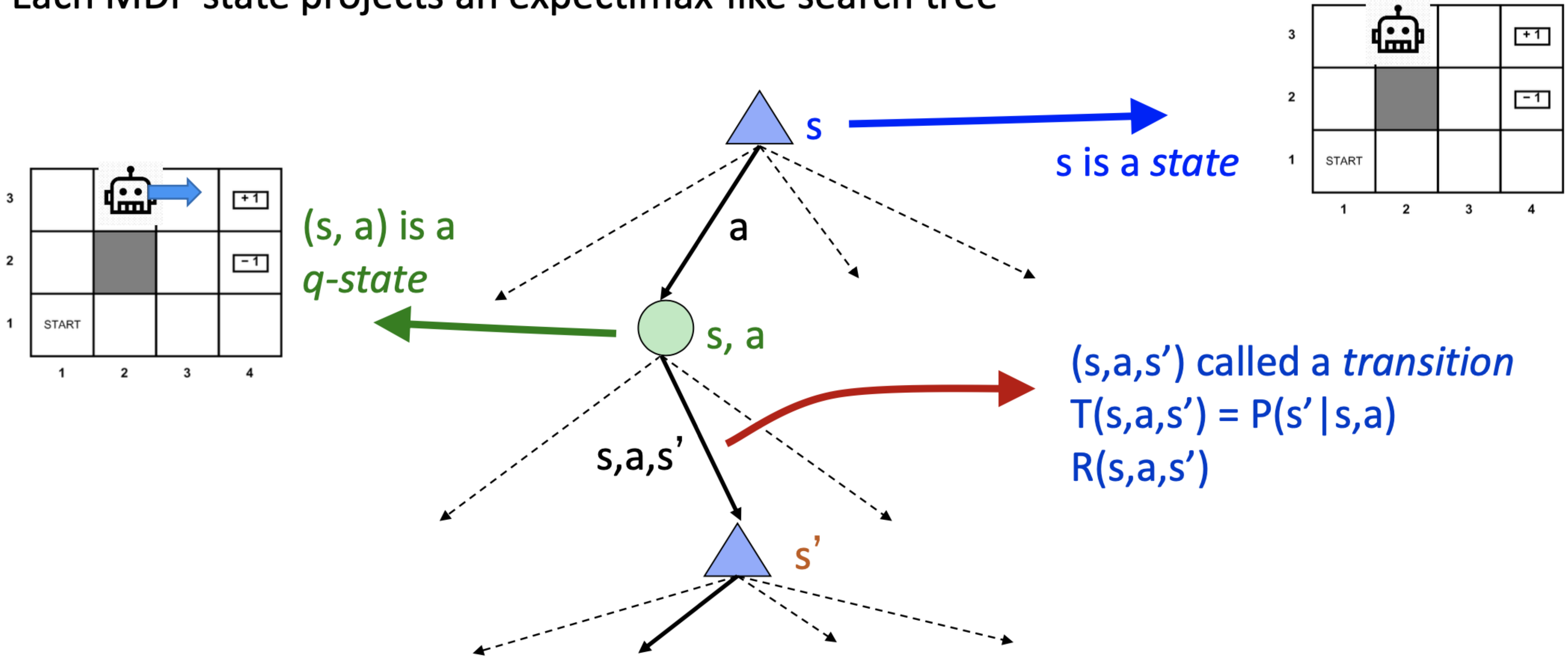


Racing car search tree



MDP search trees

Each MDP state projects an expectimax-like search tree



Utilities

Two ways to define utilities

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

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

$0 \leq \gamma \leq 1$: discount factor

What is a solution?

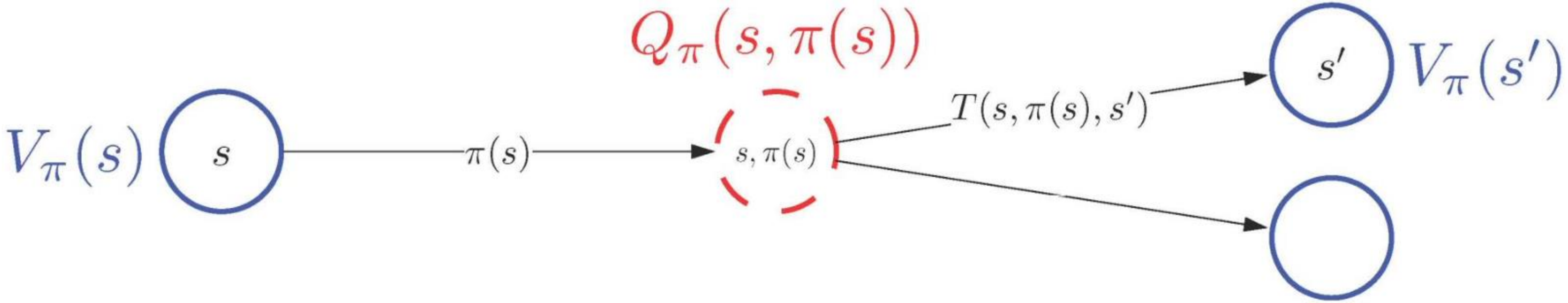
- A policy π is a mapping from each state s ∈ States to an action a ∈ Actions(s)

- Evaluating a policy
  - Following a policy yields a random path
  - The utility of a policy is the (discounted) sum of the rewards on the path (this is a random variable).
  - The value of a policy at a state is the expected utility.

Policy Evaluation

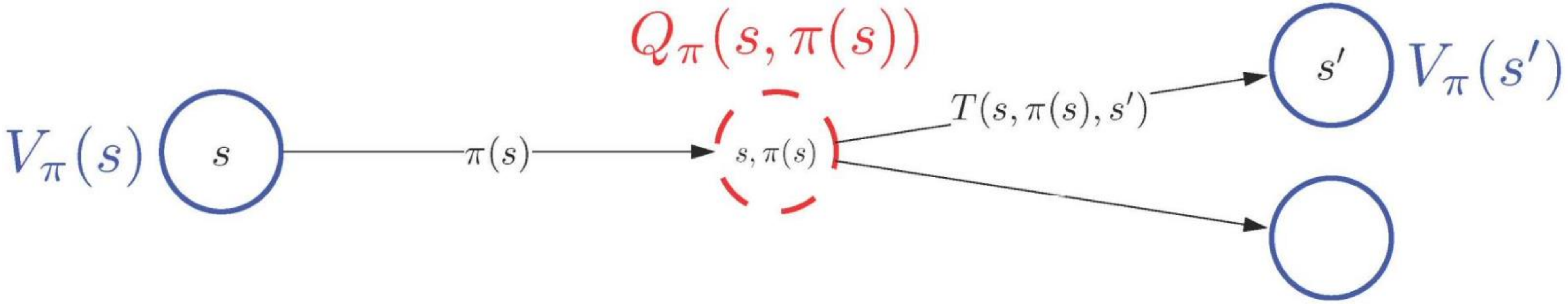
- Definition: value of a policy
  - Let $V_\pi(s)$ be the expected utility received by following policy π from state s

- Definition: Q-value of a policy
  - Let $Q_\pi(s, a)$ be the expected utility of taking action a from state s, and then following policy π



Policy Evaluation

- Plan: define recurrences relating value and Q-value



$$V_\pi(s, a) = \begin{cases} 0 \text{ } if \text{ } isEnd(s) \\ Q_\pi(s, \pi(s)) \text{ } otherwise \end{cases}$$

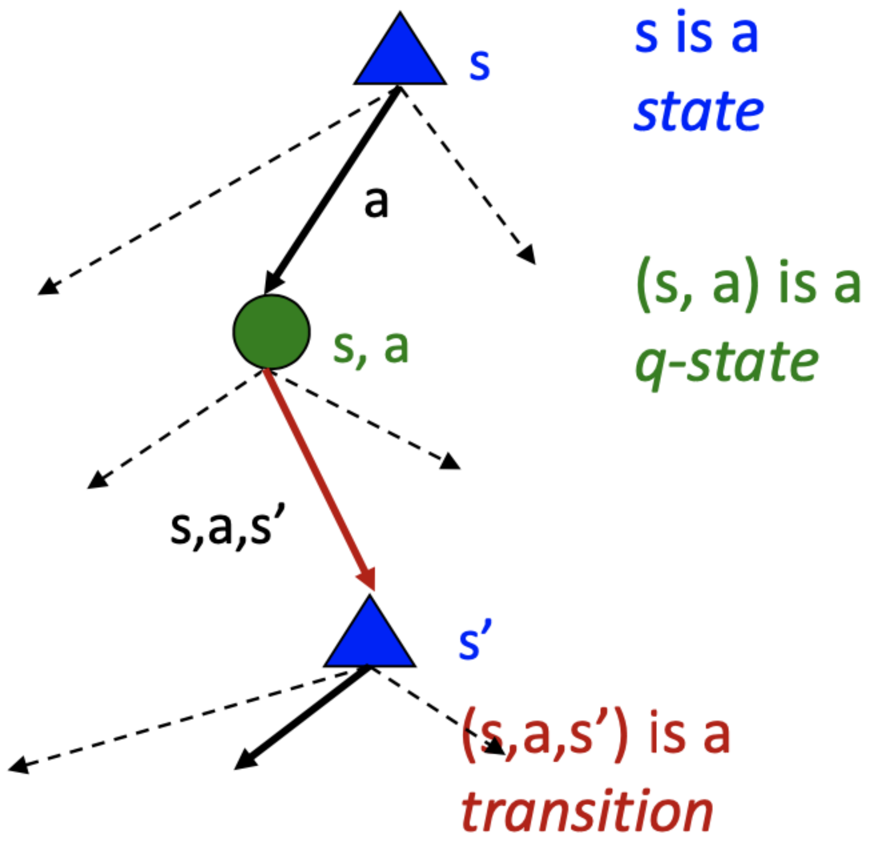
$$Q_\pi(s, a) = \sum_{s'} P(s'|s, a)[R(s, a, s') + \gamma V_\pi(s')]$$

Policy Evaluation

- Iterative algorithm: Start with arbitrary policy values and repeatedly apply recurrences to converge to true values
- Initialize $V_\pi^0(s) \leftarrow 0$ for all states s
- For iteration t = 1, … , t_{PE}
  - For each state s
    - $V_\pi^{(t)}(s) \leftarrow \sum_{s'} T(s, \pi(s), s')[R(s, \pi(s), s') + \gamma V_\pi^{(t-1)}(s')]$
- How many iterations t_{PE}?
  - Repeat until values do not change much
  - $\max_s \left| V_\pi^{(t)}(s) - V_\pi^{(t-1)}(s) \right| \leq \epsilon$

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



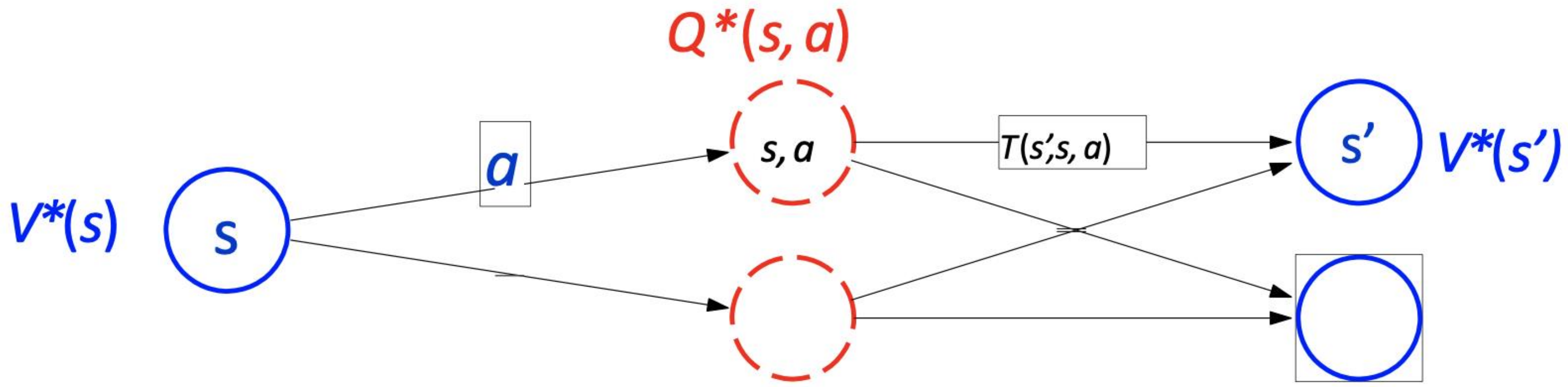
Value Function

- Value function for a policy $\pi: S \rightarrow A$
  - $V^{\pi}(s) = R(s) + \gamma \sum_{s' \in S} T(s, \pi(s), s') V^{\pi}(s')$

- Optimum value function
  - $V^{*}(s) = \max_{\pi} V^{\pi}(s)$

- $Q^{\pi}(s, a)$: the expected utility of taking action a from state s, and then following policy π.

Optimal Values and Q-values

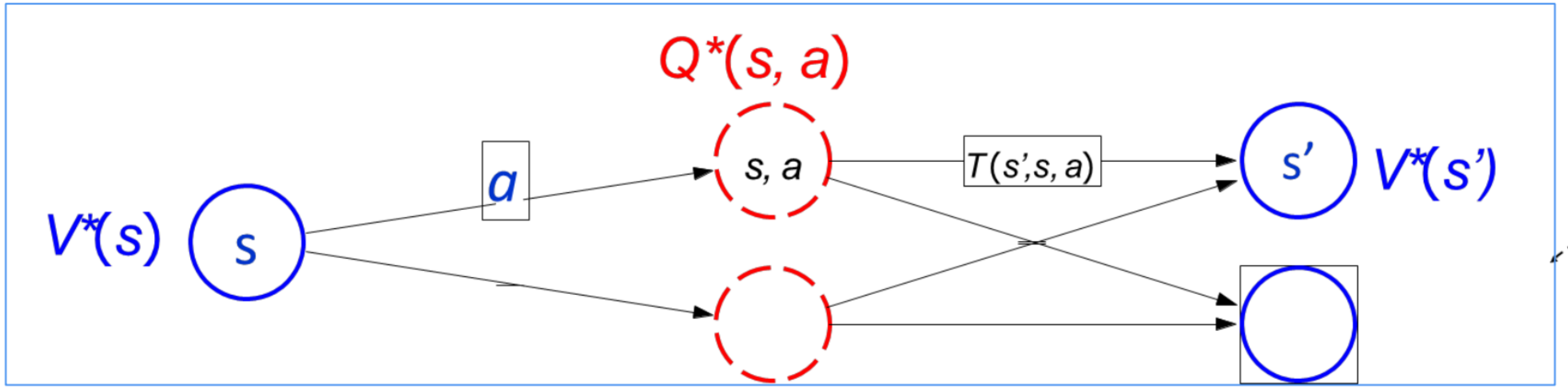


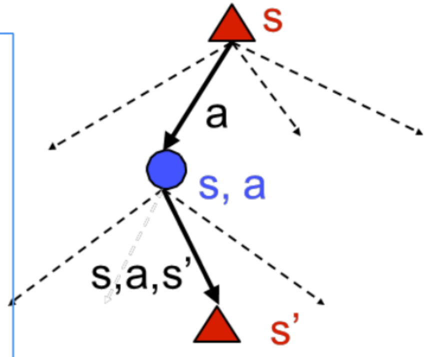
$$Q^*(s,a) = \sum_{s'} T(s,a,s') \left[R(s,a,s') + \gamma V^*(s') \right]$$

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

The Bellman Equations

- Definition of "optimal utility" leads to a simple one-step lookahead relationship amongst optimal utility values:





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

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Thank You