Robust Learning from Observation with Model Misspecification

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- 2 Dear reviewer,
- 3 here we present the results on our additional experiments evaluating the effectiveness of robust
- 4 GAILFO for perturbations different than the ones induced by a friction or mass change in MuJoCo.

5 1 The environment

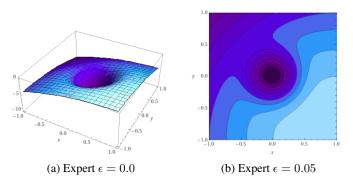


Figure 1: Schematics of the continuous gridworld environment

- 6 We consider a continuous gridworld, we denote the horizontal coordinate as x and vertical one as y.
- 7 We enforce spatial constraints, i.e. $x \in [0, 1], y \in [0, 1]$.
- 8 The agent starts in coordinates [0,1] (the upper left corner) and the episode ends when the agent
- 9 reaches the lower right region defined by the indicator function $\mathbf{1}\{x \in [0.95, 1], y \in [-1, -0.95]\}$.
- 10 The reward function is given by:

$$R(x,y) = -(x-1)^2 - (y+1)^2 - 80e^{-8(x^2+y^2)} + 10 \cdot \mathbf{1}\{x \in [0.95, 1], y \in [-1, -0.95]\} \quad (1)$$

- In addition, the actions space for the agent is given by $A = [-0.5, 0.5]^2$ and the transition dynamics
- 12 are given by:

$$s_{t+1} = \begin{cases} s_t + \frac{a_t}{10} \text{ w.p. } 1 - \epsilon \\ s_t - \frac{s_t}{10||s_t||_2} \text{ w.p. } \epsilon \end{cases}$$
 (2)

The parameter ϵ can be varied to create a dynamic mismatch.

14 1.1 Experiments

We use three experts trained with $\epsilon = 0.0, \epsilon = 0.05$ and $\epsilon = 0.1$.

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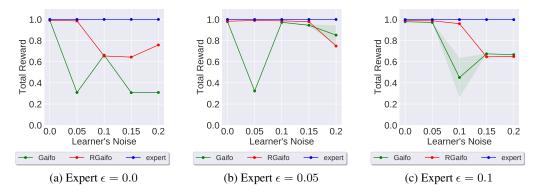


Figure 2: Comparison between Gailfo and Robust GailFO selecting the best α differently for each Learner Noise

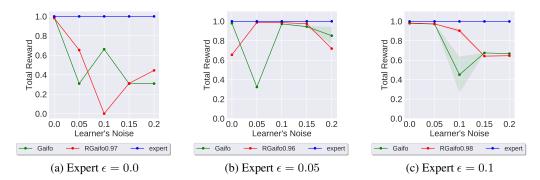


Figure 3: Comparison between Gailfo and Robust GailFO for the best selected α

- The learners act in a different environment with the following values for ϵ : 0.0, 0.05, 0.1, 0.150.2. In
- the following we report first the results of the comparison between GailFO and Robust GailFO with
- the best selected α and secondly the ablation study to assess the sensitivity to the parameter α .

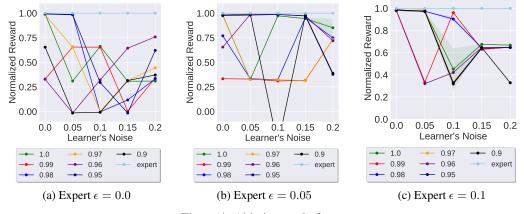


Figure 4: Ablation study for α