

## Lecture 13: Advantage Actor Critic

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# References

These slides are almost the exact copy of Practical RL course week 6 slides.  
Special thanks to YSDA team for making them publicly available.

Original slides link: [week06\\_policy\\_based](#)

# Small experiment

The next slide contains a question

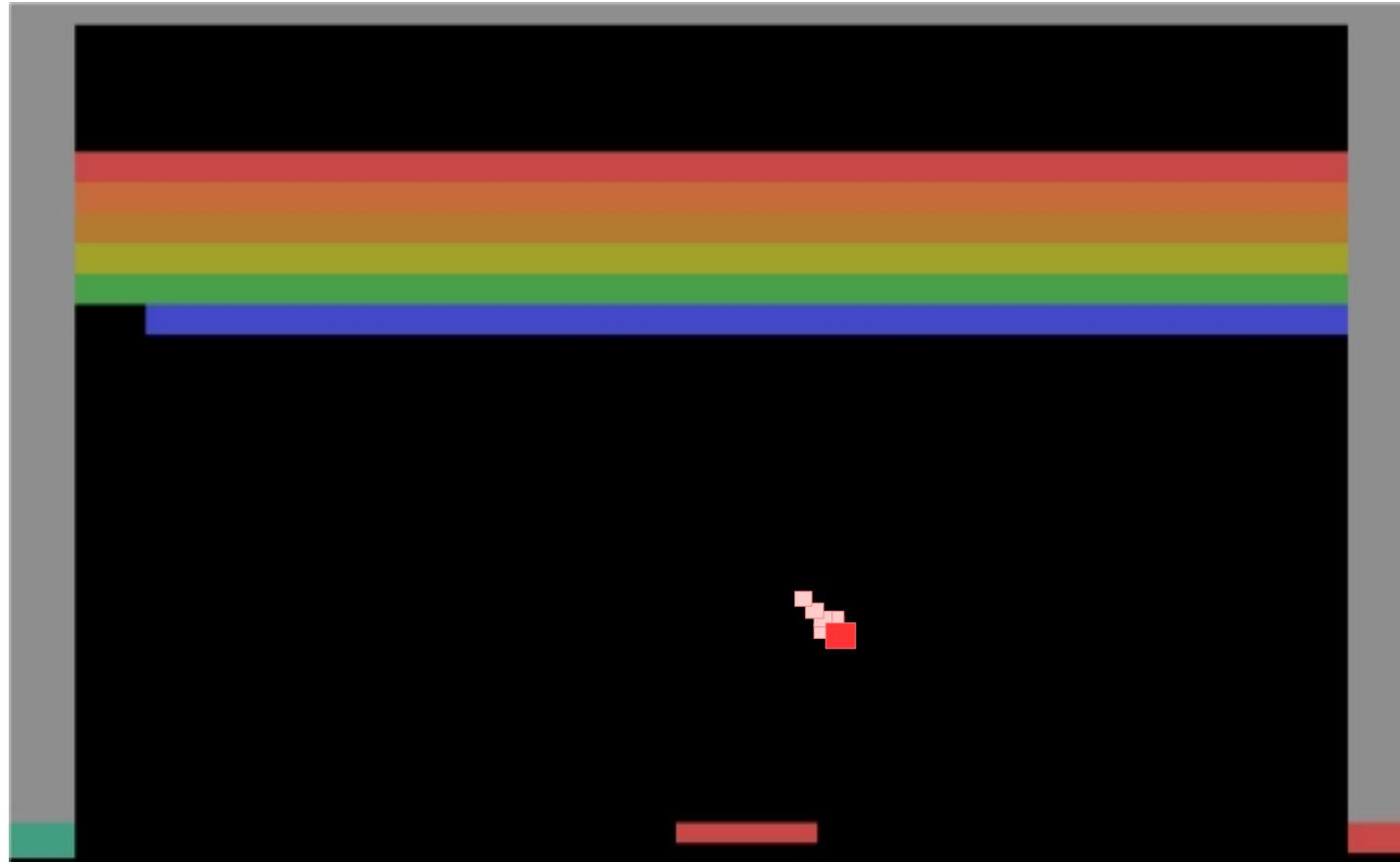
Please respond as fast as you can!

# Small experiment



left or right?

# Small experiment



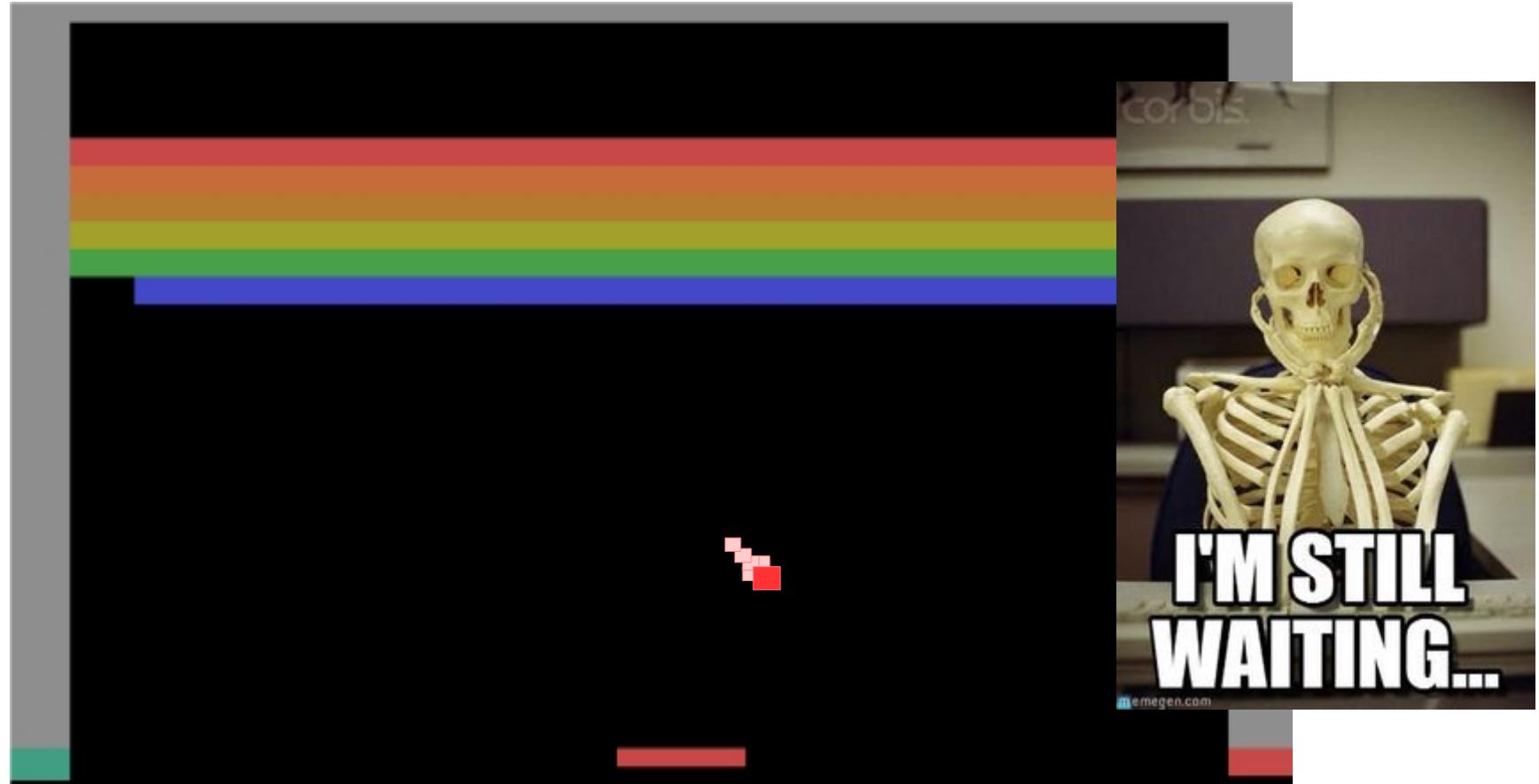
Right! Ready for next one?

# Small experiment



What's  $Q(s,\text{right})$  under  $\gamma=0.99$ ?

# Small experiment



What's  $Q(s,\text{right})$  under  $\gamma=0.99$ ?

# Approximation error

DQN is trained to minimize

$$L \approx E[Q(s_t, a_t) - (r_t + \gamma \cdot \max_{a'} Q(s_{t+1}, a'))]^2$$

**Simple 2-state world**

	True	(A)	(B)
$Q(s_0, a_0)$	1	1	2
$Q(s_0, a_1)$	2	2	1
$Q(s_1, a_0)$	3	3	3
$Q(s_1, a_1)$	100	50	100

Q: Which prediction is better (A/B)?

# Approximation error

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$Q(s_1, a_1)$	100	50	100

better policy      less MSE

# Approximation error

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Simple 2-state world

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$Q(s_1, a_0)$	3	3	3
$Q(s_1, a_1)$	100	50	100

Q-learning will prefer worse policy (B)!

better  
policy

less  
MSE

# Conclusion

- Often computing q-values is harder than picking optimal actions!
- We could avoid learning value functions by directly learning agent's policy  $\pi_\theta(a|s)$

**Q:** what algorithm works that way?  
(of those we studied)

# Conclusion

- Often computing q-values is harder than picking optimal actions!
- We could avoid learning value functions by directly learning agent's policy  $\pi_\theta(a|s)$

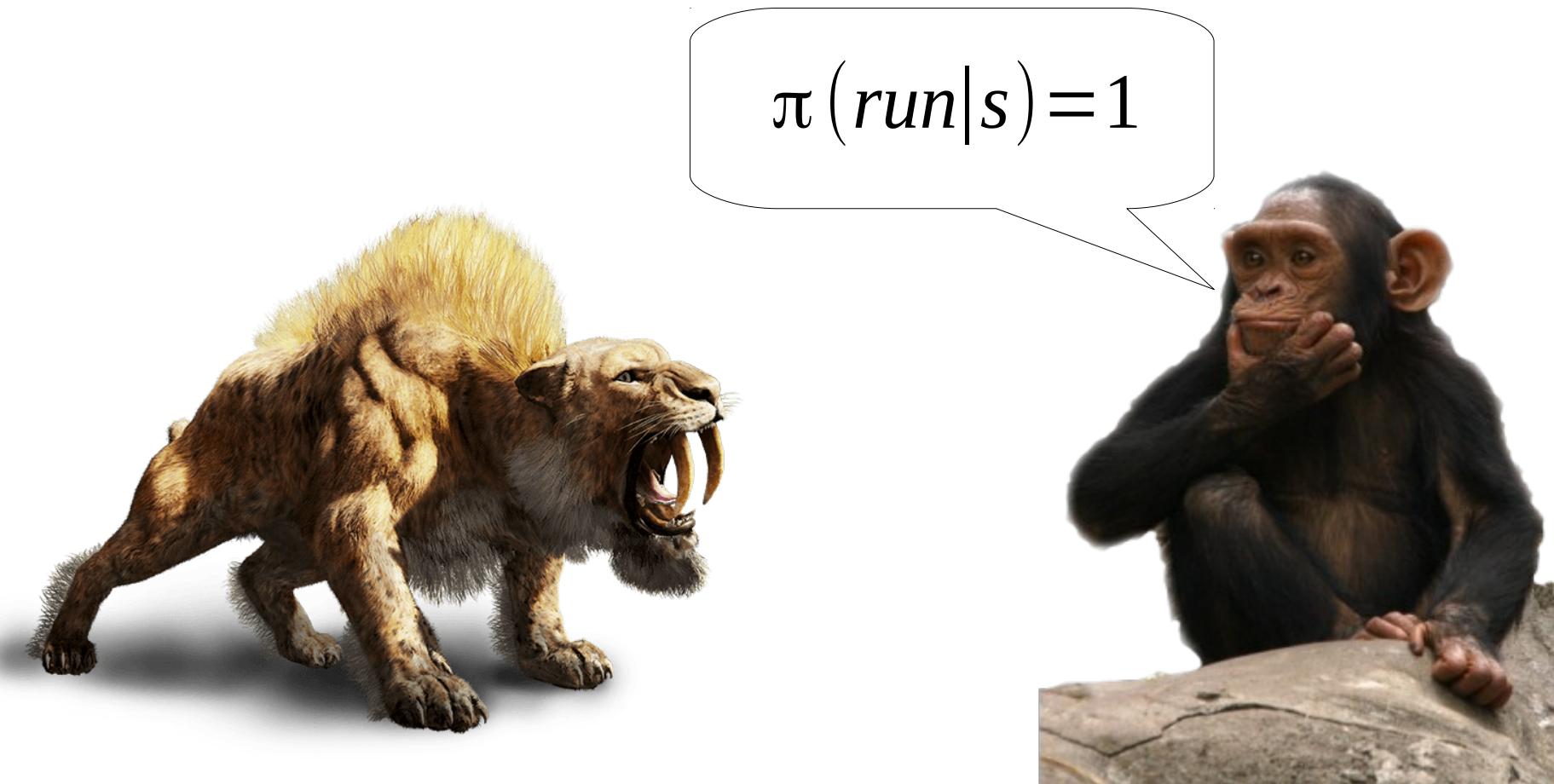
**Q:** what algorithm works that way?

**e.g. crossentropy method**

# NOT how humans survived



# how humans survived



# Policies

In general, two kinds

- Deterministic policy

$$a = \pi_\theta(s)$$

- Stochastic policy

$$a \sim \pi_\theta(a|s)$$

Q: Any case where stochastic is better?

# Policies

In general, two kinds

- Deterministic policy

$$a = \pi_\theta(s)$$

- Stochastic policy

$$a \sim \pi_\theta(a|s)$$

e.g. rock-paper  
-scissors

Q: Any case where stochastic is better?

# Policies

In general, two kinds

- Deterministic policy

Genetic algos (week 0)  
Deterministic policy gradient

$$a = \pi_{\theta}(s)$$

same action each time

- Stochastic policy

Crossentropy method  
Policy gradient

$$a \sim \pi_{\theta}(a|s)$$

sampling takes care  
of exploration

Q: how to represent policy in continuous action space?

# Policies

In general, two kinds

- Deterministic policy

Genetic algos (week 0)  
Deterministic policy gradient

$$a = \pi_{\theta}(s)$$

same action each time

- Stochastic policy

Crossentropy method  
Policy gradient

$$a \sim \pi_{\theta}(a|s)$$

sampling takes care  
of exploration

categorical, normal, mixture of normal, whatever

# Two approaches

- **Value based:**

Learn value function

$$Q_\theta(s, a) \text{ or } V_\theta(s)$$

Infer policy

$$a = \underset{a}{\operatorname{argmax}} Q_\theta(s, a)$$

- **Policy based:**

Explicitly learn policy

$$\pi_\theta(a|s) \text{ or } \pi_\theta(s) \rightarrow a$$

Implicitly maximize reward over policy

# Recap: crossentropy method

- Initialize NN weights  $\theta_0 \leftarrow random$
- Loop:
  - Sample N sessions
  - elite = take M best sessions and concatenate

$$\theta_{i+1} = \theta_i + \alpha \nabla \sum_i \log \pi_{\theta_i}(a_i | s_i) \cdot [s_i, a_i \in Elite]$$

# Recap: crossentropy method

- Initialize NN weights  $\theta_0 \leftarrow random$
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TD version: elite (s,a) that have highest G(s,a)  
(select elites independently from each state)

# Policy gradient main idea

Why so complicated?

We'd rather maximize reward directly!

# Objective

Expected reward:

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a, s', a', \dots)$$

...

Expected discounted reward:

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} G(s, a)$$

# Objective

Expected reward:  $R(z)$  setting

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a, s', a', \dots)$$

...

Expected discounted reward:  $G(s, a) = r + \gamma^* G(s', a')$

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} G(s, a)$$

# Objective

Consider an 1-step process for simplicity

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

# Objective

Consider an 1-step process for simplicity

$$J = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

s

a

Reward for 1-step  
session

state visitation frequency  
(may depend on policy)

Q: how do we compute that?

# Objective

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

$$J \approx \frac{1}{N} \sum_{i=0}^N R(s, a)$$

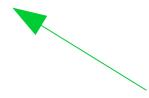


sample N sessions  
under current policy

# Objective

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

$$J \approx \frac{1}{N} \sum_{i=0}^N R(s, a)$$



sample N sessions

Can we optimize policy now?

# Objective

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

parameters “sit” here



$$J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s, a \in z_i} R(s, a)$$

We don't know how to compute  $dJ/d\theta$

# Optimization

## Finite differences

- Change policy a little, evaluate

$$\nabla J \approx \frac{J_{\theta+\epsilon} - J_\theta}{\epsilon}$$

## Stochastic optimization

- Good old crossentropy method
- Maximize probability of “elite” actions

# Optimization

## Finite differences

- Change policy a little, evaluate

$$\nabla J \approx \frac{J_{\theta+\epsilon} - J_\theta}{\epsilon}$$

## Stochastic optimization

- Good old crossentropy method
- Maximize probability of “elite” actions

Q: any problems with those two?

# Optimization

## Finite differences

- Change policy a little, evaluate

$$\nabla J \approx \frac{J_{\theta+\epsilon} - J_\theta}{\epsilon}$$

VERY noisy, especially  
if both  $J$  are sampled

## Stochastic optimization

- Good old crossentropy method
- Maximize probability of “elite” actions

“quantile convergence”  
problems with stochastic  
MDPs

# Objective

$$J = \underset{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}}{E} R(s, a) = \int_s p(s) \int_a \pi_\theta(a|s) R(s, a) da ds$$

Wish list:

- Analytical gradient
- Easy/stable approximations

# Logderivative trick

Simple math

$$\nabla \log \pi(z) = ???$$

(try chain rule)

# Logderivative trick

Simple math

$$\nabla \log \pi(z) = \frac{1}{\pi(z)} \cdot \nabla \pi(z)$$

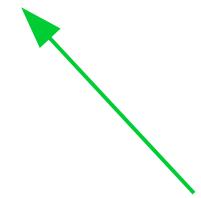
$$\pi \cdot \nabla \log \pi(z) = \nabla \pi(z)$$

# Policy gradient

## Analytical inference

$$\nabla J = \int_s p(s) \int_a \nabla \pi_\theta(a|s) R(s, a) da ds$$

$$\pi \cdot \nabla \log \pi(z) = \nabla \pi(z)$$



# Policy gradient

## Analytical inference

$$\nabla J = \int_s p(s) \int_a \nabla \pi_\theta(a|s) R(s, a) da ds$$

$$\pi \cdot \nabla \log \pi(z) = \nabla \pi(z)$$

$$\nabla J = \int_s p(s) \int_a \pi_\theta(a|s) \nabla \log \pi_\theta(a|s) R(s, a) da ds$$

Q: anything curious about that formula?

# Policy gradient

## Analytical inference

$$\nabla J = \int_s p(s) \int_a \nabla \pi_\theta(a|s) R(s, a) da ds$$

$$\pi \cdot \nabla \log \pi(z) = \nabla \pi(z)$$

$$\nabla J = \int_s p(s) \int_a \pi_\theta(a|s) \nabla \log \pi_\theta(a|s) R(s, a) da ds$$

that's expectation :)

# REINFORCE (bandit)

- Initialize NN weights  $\theta_0 \leftarrow \text{random}$
- Loop:
  - Sample N sessions  $\mathbf{z}$  under current
  - Evaluate policy gradient

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \nabla \log \pi_\theta(a|s) \cdot R(s, a)$$

- Ascend  $\theta_{i+1} \leftarrow \theta_i + \alpha \cdot \nabla J$

# Discounted reward case

- Replace R with Q :)

$$\nabla J = \int_s p(s) \int_a \nabla \pi_\theta(a|s) Q(s, a) da ds$$

**True action value**  
a.k.a.  $E[G(s, a)]$

$$\pi \cdot \nabla \log \pi(z) = \nabla \pi(z)$$

$$\nabla J = \int_s p(s) \int_a \pi_\theta(a|s) \nabla \log \pi_\theta(a|s) Q(s, a) da ds$$

**that's expectation :)**

# REINFORCE (discounted)

- Policy gradient

$$\nabla J = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(s|a)}} \nabla \log \pi_\theta(a|s) \cdot Q(s, a)$$

- Approximate with sampling

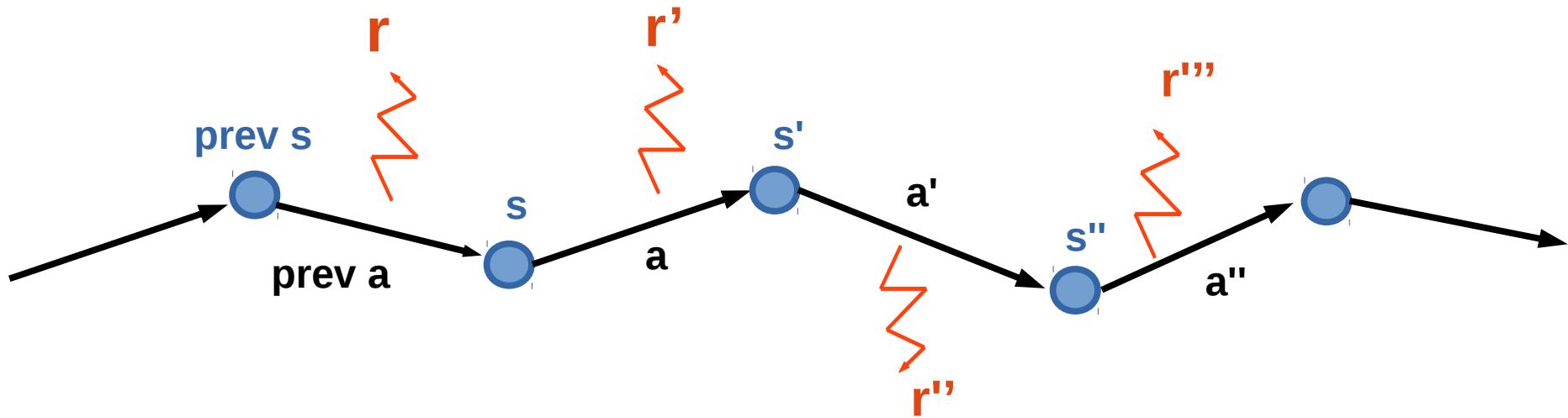
$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s, a \in z_i} \nabla \log \pi_\theta(a|s) \cdot Q(s, a)$$

# REINFORCE algorithm

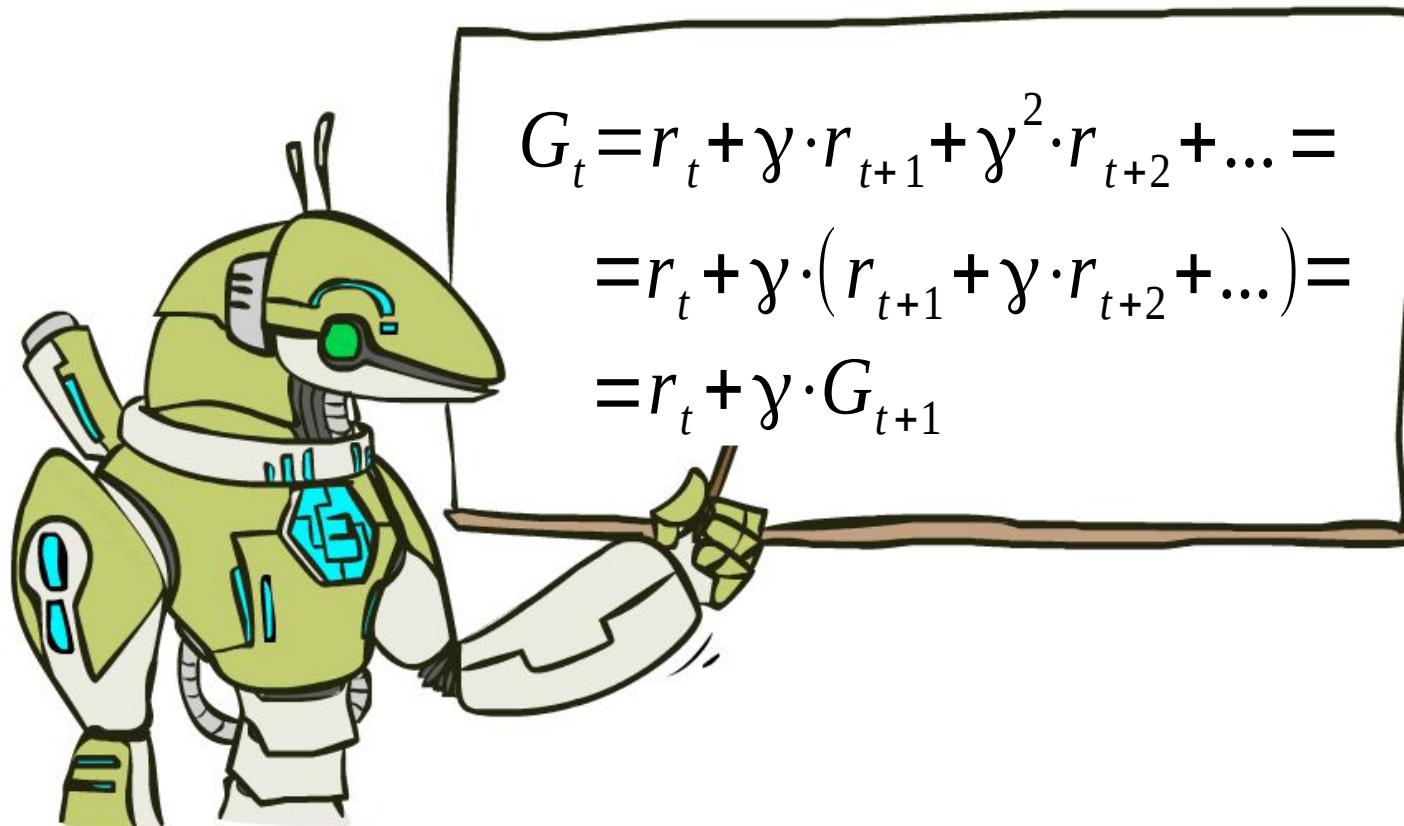
We can estimate Q using G

$$Q_{\pi}(s_t, a_t) = E_s \cdot G(s_t, a_t)$$

$$G_t = r_t + \gamma \cdot r_{t+1} + \gamma^2 \cdot r_{t+2} + \dots$$



# Recap: discounted rewards



We can use this to compute all  $G$ 's  
in linear time

# REINFORCE algorithm

- Initialize NN weights  $\theta_0 \leftarrow \text{random}$
- Loop:
  - Sample N sessions  $\mathbf{z}$  under current  $\pi_\theta(a|s)$
  - Evaluate policy gradient

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot Q(s,a)$$

- Ascend  $\theta_{i+1} \leftarrow \theta_i + \alpha \cdot \nabla J$

# REINFORCE algorithm

- Initialize NN weights  $\theta_0 \leftarrow \text{random}$   
**Q:** is it off- or on-policy?
- Loop:
  - Sample N sessions  $\mathbf{z}$  under current  $\pi_\theta(a|s)$
  - Evaluate policy gradient

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot Q(s,a)$$

- Ascend  $\theta_{i+1} \leftarrow \theta_i + \alpha \cdot \nabla J$

# REINFORCE algorithm

- Initialize NN weights  $\theta_0 \leftarrow \text{random}$
- Loop:
  - Sample N sessions  $\mathbf{z}$  under current policy  
 $\pi_\theta(a|s)$
  - Evaluate policy gradient

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot Q(s,a)$$

- Ascend  $\theta_{i+1} \leftarrow \theta_i + \alpha \cdot \nabla J$

# value-based Vs policy-based

## Value-based

- Q-learning, SARSA, MCTS  
value-iteration
- Solves harder problem
- Artificial exploration
- Learns from partial experience  
(temporal difference)
- Evaluates strategy for free :)

## Policy-based

- REINFORCE, CEM
- Solves easier problem
- Innate exploration
- Innate stochasticity
- Support continuous action space
- Learns from full session only?



# value-based Vs policy-based

## Value-based

- Q-learning, SARSA, MCTS  
value-iteration
- Solves harder problem
- Artificial exploration
- Learns from partial experience  
(temporal difference)
- Evaluates strategy for free :)

## Policy-based

- REINFORCE, CEM
- We'll learn much more soon!
- Solves easier problem
  - Innate exploration
  - Innate stochasticity
  - Support continuous action space
  - ~~Learns from full session only~~



# REINFORCE baselines

- Initialize NN weights  $\theta_0 \leftarrow \text{random}$
- Loop:
  - Sample N sessions  $\mathbf{z}$  under current  $\pi_\theta(a|s)$
  - Evaluate policy gradient

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot Q(s,a)$$

**What is better for learning:**  
**random action in good state**  
**or**  
**great action in bad state?**

# REINFORCE baselines

We can subtract arbitrary baseline  $b(s)$

$$\nabla J = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) (Q(s, a) - b(s)) = \dots$$

$$\dots = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) Q(s, a) - E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) b(s) = \dots$$

# REINFORCE baselines

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Q: Can you simplify the second term?

Note that  $b(s)$  does not depend on  $a$

# REINFORCE baselines

We can subtract arbitrary baseline  $b(s)$

$$\nabla J = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) (Q(s, a) - b(s)) = \dots$$

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$$E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) b(s) = b(s) \cdot E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) = 0$$

# REINFORCE baselines

We can subtract arbitrary baseline  $b(s)$

$$\nabla J = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) (Q(s, a) - b(s)) = \dots$$

$$\dots = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) Q(s, a) - E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) b(s) = \dots$$

**Gradient direction doesn't change!**

$$\dots = E_{\substack{s \sim p(s) \\ a \sim \pi_\theta(a|s)}} \nabla \log \pi_\theta(a|s) Q(s, a)$$

# REINFORCE baselines

- Gradient direction  $\nabla J$  stays the same
- Variance may change

Gradient variance:  $Var[Q(s, a) - b(s)]$   
as a *random variable over  $(s, a)$*

$$Var[Q(s, a)] - 2 \cdot Cov[Q(s, a), b(s)] + Var[b(s)]$$

# REINFORCE baselines

- Gradient direction  $\nabla J$  stays the same
- Variance may change

Gradient variance:  $\text{Var}[Q(s, a) - b(s)]$   
as a *random variable over  $(s, a)$*

$$\text{Var}[Q(s, a)] - 2 \cdot \text{Cov}[Q(s, a), b(s)] + \text{Var}[b(s)]$$



If  $b(s)$  correlates with  $Q(s, a)$ , variance decreases

# REINFORCE baselines

- Gradient direction  $\nabla J$  stays the same
- Variance may change

Gradient variance:  $\text{Var}[Q(s, a) - b(s)]$   
as a *random variable over  $(s, a)$*

$$\text{Var}[Q(s, a)] - 2 \cdot \text{Cov}[Q(s, a), b(s)] + \text{Var}[b(s)]$$



Q: can you suggest any such  $b(s)$ ?

# REINFORCE baselines

- Gradient direction  $\nabla J$  stays the same
- Variance may change

Gradient variance:  $\text{Var}[Q(s, a) - b(s)]$   
as a *random variable over  $(s, a)$*

$$\text{Var}[Q(s, a)] - 2 \cdot \text{Cov}[Q(s, a), b(s)] + \text{Var}[b(s)]$$

**Naive baseline:**  $b$  = moving average  $Q$   
over all  $(s, a)$ ,  $\text{Var}[b(s)] = 0$ ,  $\text{Cov}[Q, b] > 0$

# REINFORCE baselines

Better baseline:  $b(s) = V(s)$

$$\nabla J \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot (Q(s,a) - V(s))$$

**Q:** but how do we predict  $V(s)$ ?

# Actor-critic

- Learn both  $V(s)$  and  $\pi_\theta(a|s)$
- Hope for the best of both worlds :)



# Advantage actor-critic

Idea: learn both  $\pi_\theta(a|s)$  and  $V_\theta(s)$

Use  $V_\theta(s)$  to learn  $\pi_\theta(a|s)$  faster!

Q: how can we estimate  $A(s,a)$  from  $(s,a,r,s')$  and V-function?

# Advantage actor-critic

Idea: learn both  $\pi_\theta(a|s)$  and  $V_\theta(s)$

Use  $V_\theta(s)$  to learn  $\pi_\theta(a|s)$  faster!

$$A(s, a) = Q(s, a) - V(s)$$

$$Q(s, a) = r + \gamma \cdot V(s')$$

$$A(s, a) = r + \gamma \cdot V(s') - V(s)$$

# Advantage actor-critic

Idea: learn both  $\pi_\theta(a|s)$  and  $V_\theta(s)$

Use  $V_\theta(s)$  to learn  $\pi_\theta(a|s)$  faster!

$$A(s, a) = Q(s, a) - V(s)$$

$$Q(s, a) = r + \gamma \cdot V(s')$$

$$A(s, a) = r + \gamma \cdot V(s') - V(s)$$

Also: n-step  
version

# Advantage actor-critic

Idea: learn both  $\pi_\theta(a|s)$  and  $V_\theta(s)$

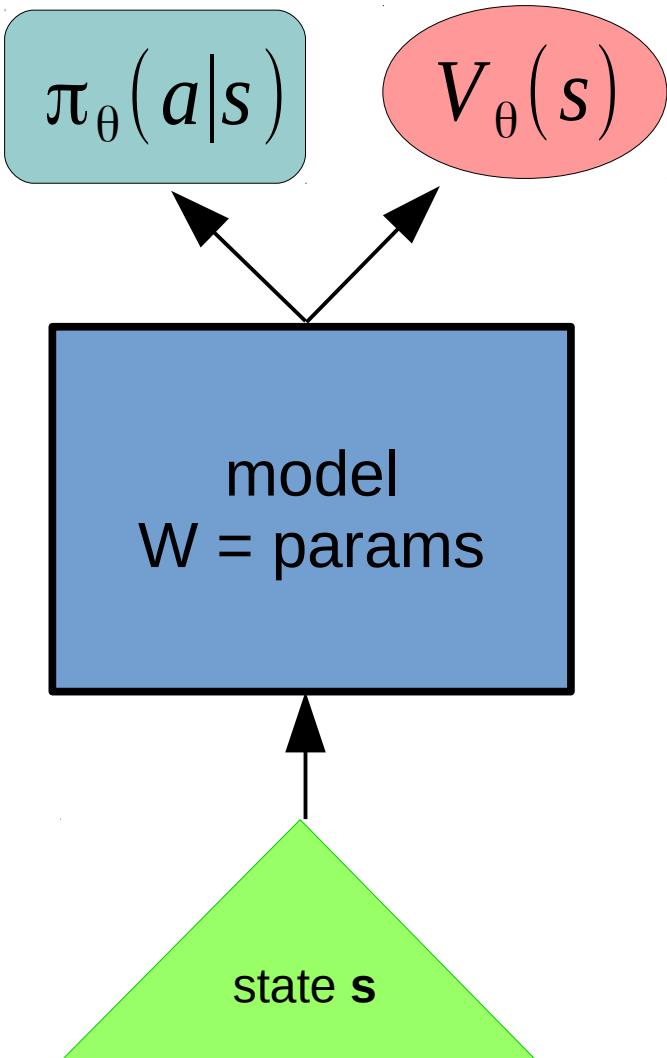
Use  $V_\theta(s)$  to learn  $\pi_\theta(a|s)$  faster!

$$A(s, a) = r + \gamma \cdot V(s') - V(s)$$

$$\nabla J_{actor} \approx \frac{1}{N} \sum_{i=0}^N \sum_{s, a \in z_i} \nabla \log \pi_\theta(a|s) \cdot \underline{\underline{A(s, a)}}$$

consider  
const

# Advantage actor-critic



Improve policy:

$$\nabla J_{actor} \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} \nabla \log \pi_\theta(a|s) \cdot A(s, a)$$

Improve value:

$$L_{critic} \approx \frac{1}{N} \sum_{i=0}^N \sum_{s,a \in z_i} (V_\theta(s) - [r + \gamma \cdot V(s')])^2$$

# Continuous action spaces

What if there's continuously many actions?

- Robot control: control motor voltage
  - Trading: assign money to equity

How does the algorithm change?

# Continuous action spaces

What if there's continuously many actions?

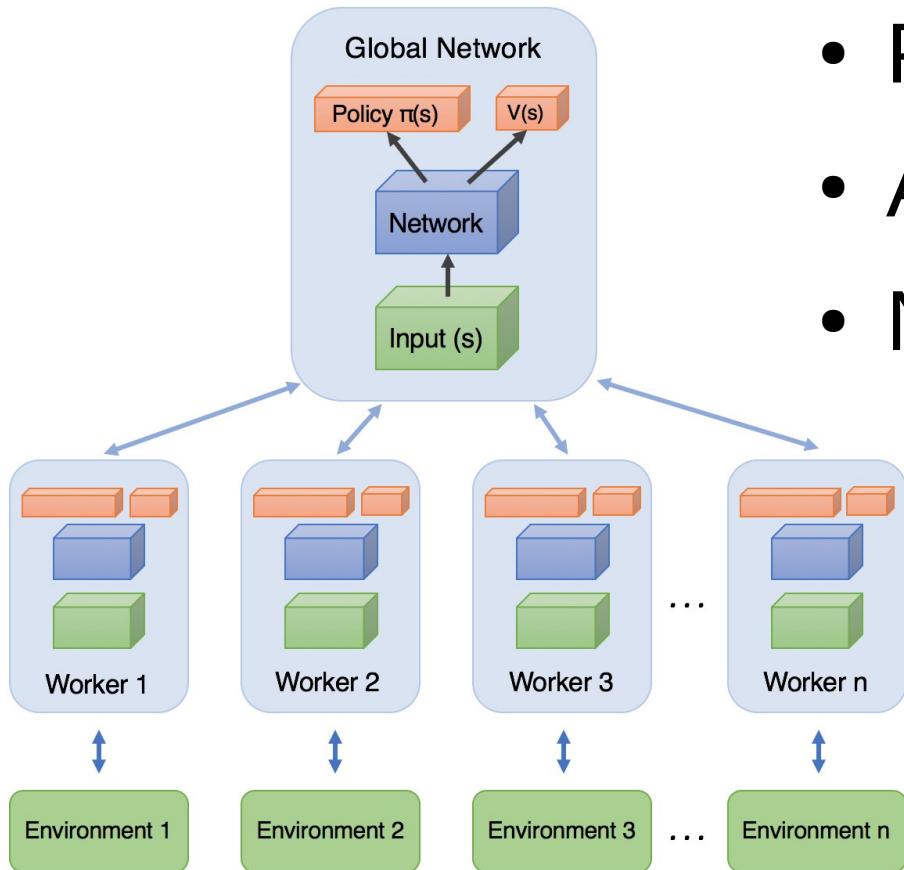
- Robot control: control motor voltage
  - Trading: assign money to equity

How does the algorithm change?

it doesn't :)

Just plug in a different formula for  
 $\pi(a|s)$ , e.g. normal distribution

# Asynchronous advantage actor-critic

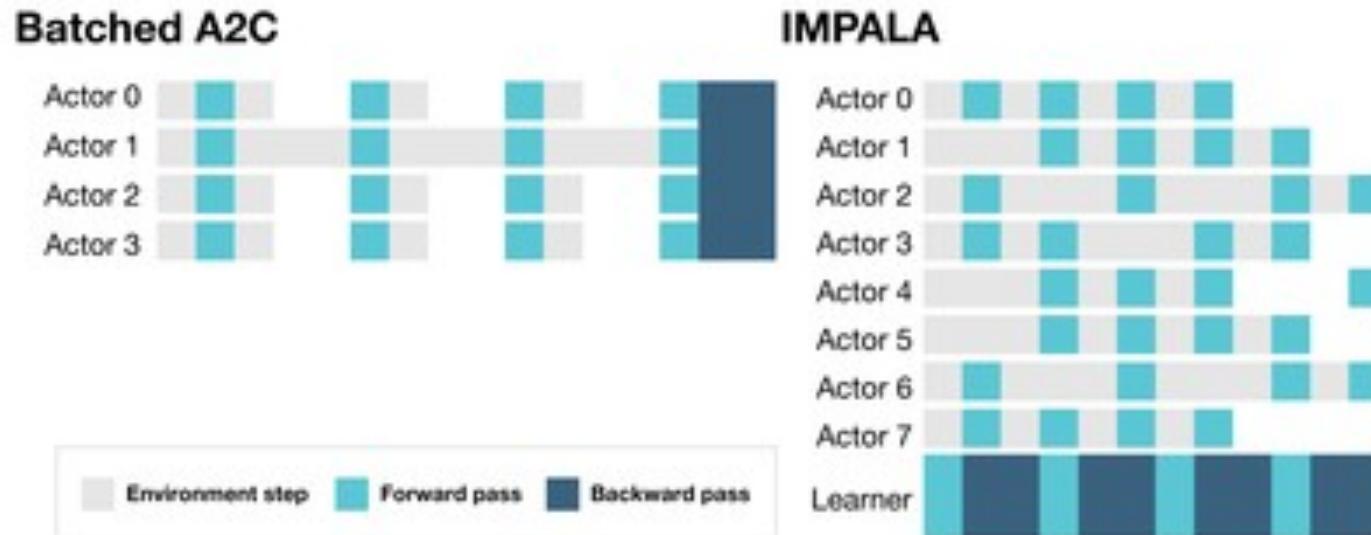


- Parallel game sessions
- Async multi-CPU training
- No experience replay
- LSTM policy
- N-step advantage
- No experience replay

Read more: <https://arxiv.org/abs/1602.01783>

# IMPALA

- Massively parallel
- Separate actor / learner processes
  - Small experience replay w/ importance sampling



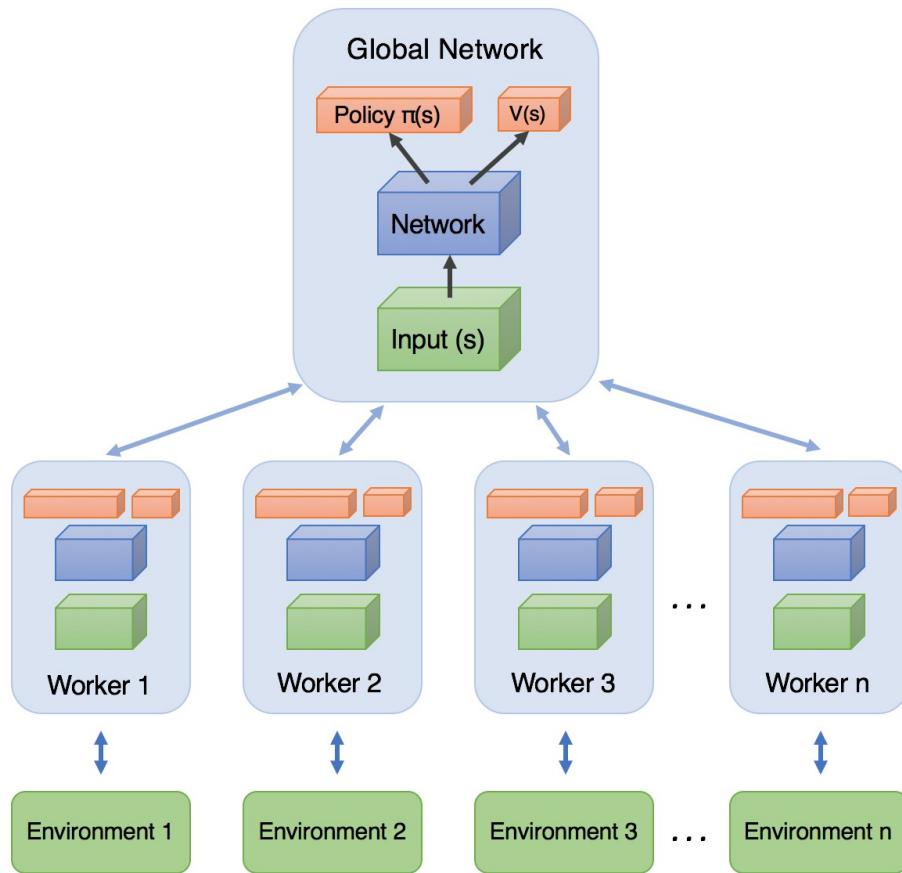
Read more: <https://arxiv.org/abs/1802.01561>

# Duct tape zone

- $V(s)$  errors less important than in Q-learning
  - actor still learns even if critic is random, just slower
- Regularize with entropy
  - to prevent premature convergence
- Learn on parallel sessions
  - Or super-small experience replay
- Use logsoftmax for numerical stability



# Asynchronous advantage actor-critic



- Remember log-derivative trick
- Combining best from both worlds is generally a good idea
- See [this](#) paper for the proof of the policy gradient for discounted rewards
- Time to write some code!