

Representation Matters: Offline Representation Learning for Sequential Decision Making

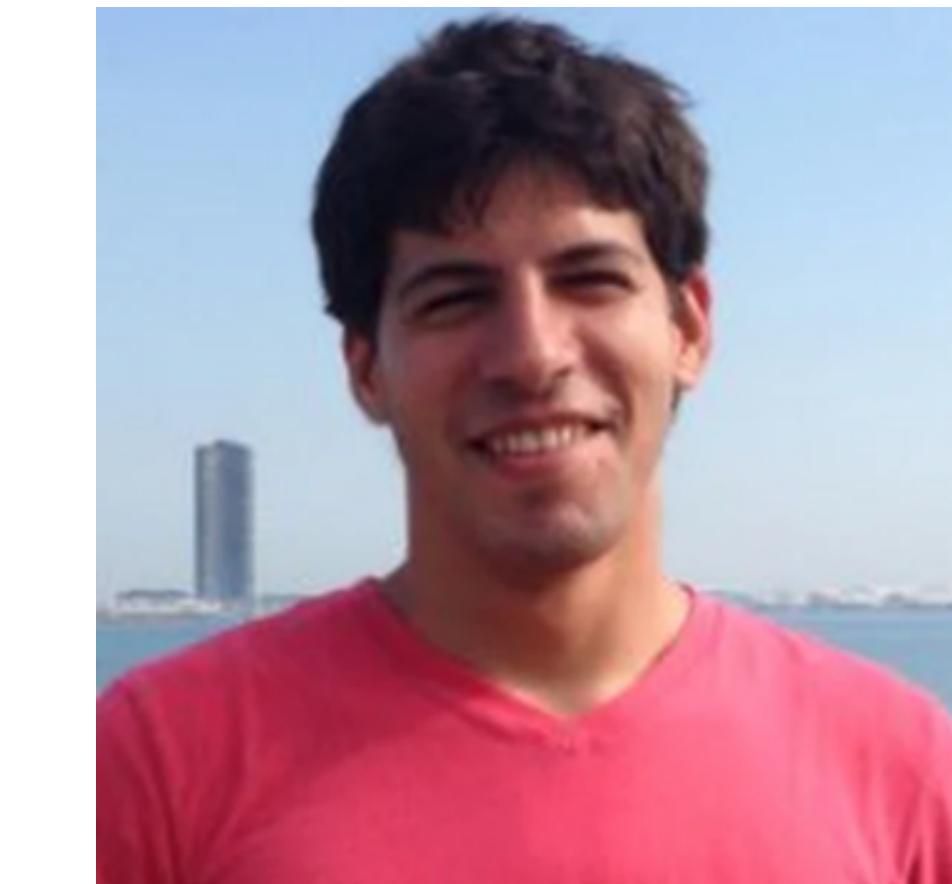
Sherry Yang

sherryy@



Ofir Nachum

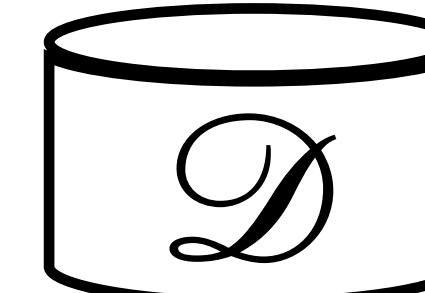
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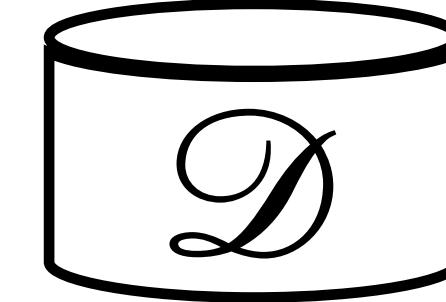
Paper: <https://arxiv.org/abs/2102.05815>

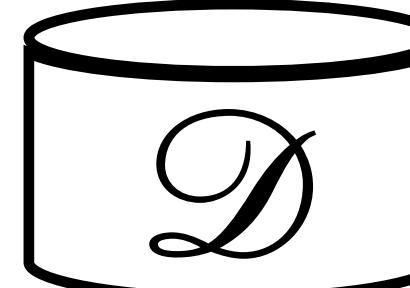
Code: https://github.com/google-research/google-research/tree/master/rl_repr

Representation Learning on Offline Data

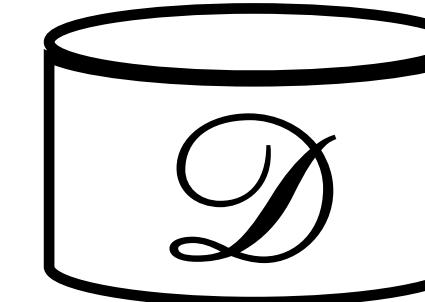
Given a fixed set of experience  , what can we do?

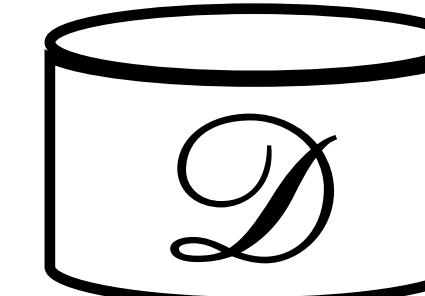
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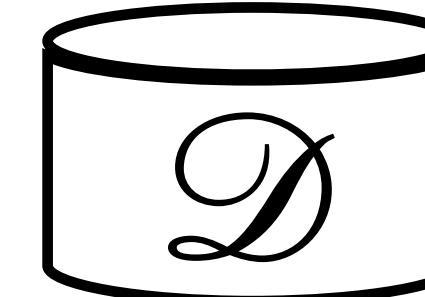
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- Offline reinforcement learning:  $\rightarrow \pi(\cdot | s)$

Representation Learning on Offline Data

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- Offline reinforcement learning:  $\rightarrow \pi(\cdot | s)$

- Offline representation learning:  $\rightarrow \phi(s)$

Downstream tasks

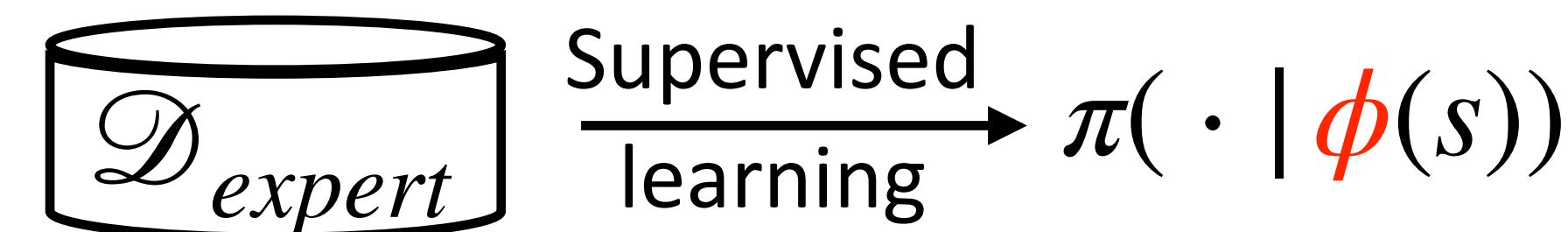
Representation Learning on Offline Data

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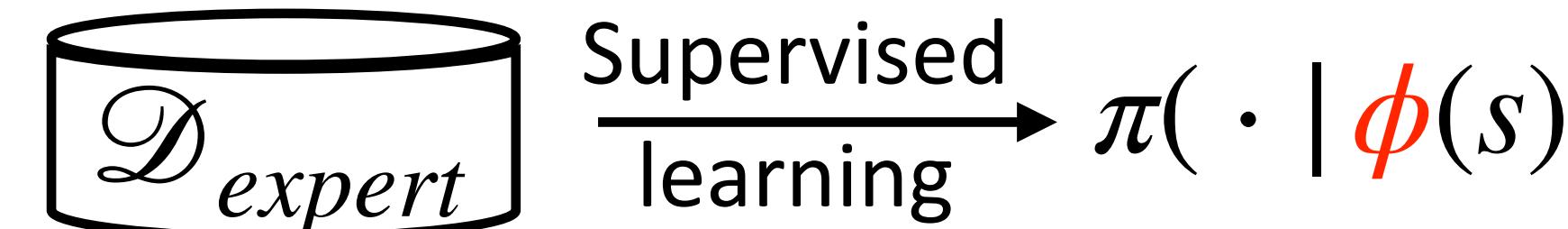
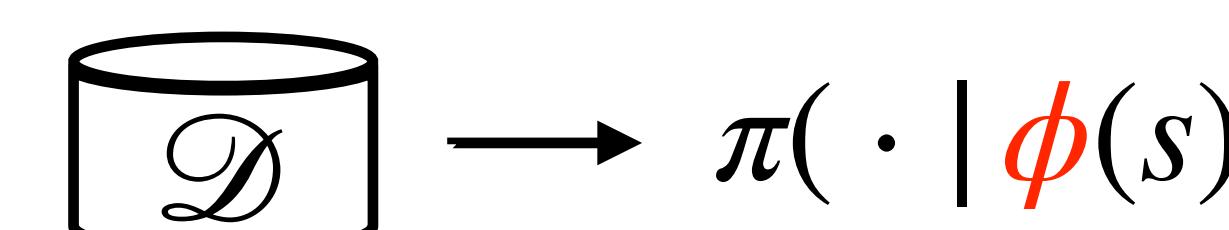
- Imitation in low-data regime:



Limited expert demonstration, much undirected experience

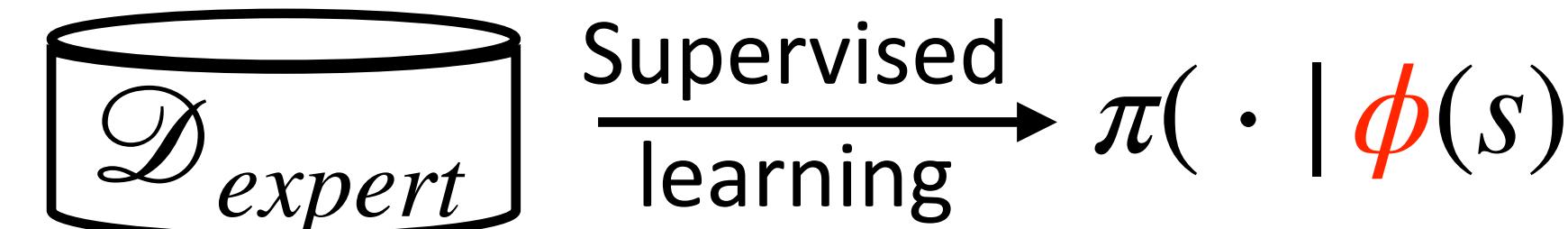
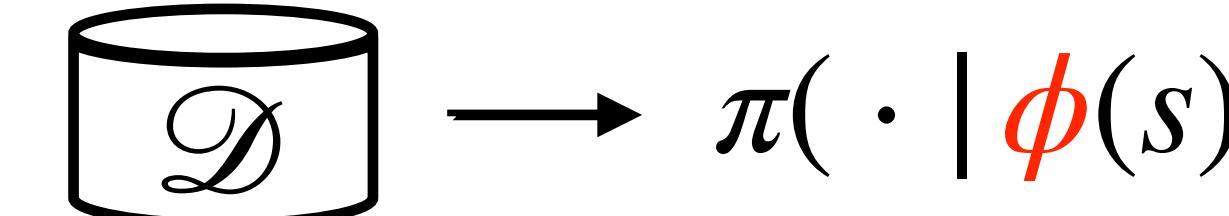
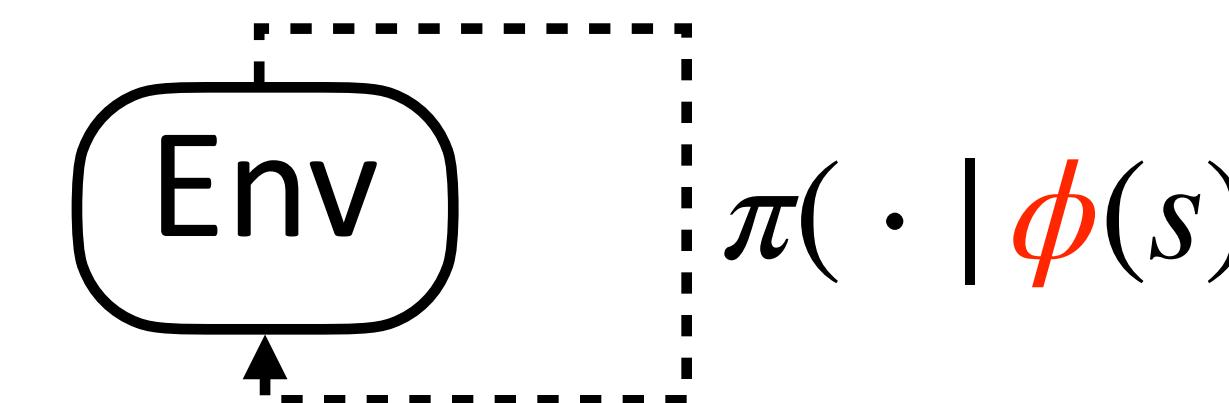
Representation Learning on Offline Data

What kind of downstream tasks might benefit from representation learning?

- Imitation in low-data regime:  $\xrightarrow[\text{Supervised learning}]{\quad} \pi(\cdot | \phi(s))$
Limited expert demonstration, much undirected experience
- Offline RL:  $\xrightarrow{\quad} \pi(\cdot | \phi(s))$
Expensive/unavailable environments (e.g., recommendation systems)

Representation Learning on Offline Data

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Limited expert demonstration, much undirected experience
- Offline RL:

Expensive/unavailable environments (e.g., recommendation systems)
- Online RL:

Potentially in partially observable environments

Representation Learning Objectives

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Forward latent model (DeepMDP): $\|r_t - g(\phi(s_t), a_t)\|^2 - \log P(\phi(s_{t+1})|f(\phi(s_t), a_t))$

Forward energy model:
$$\frac{\rho(s_{t+1}) \exp\{\phi(s_{t+1})^\top W f(\phi(s_t), a_t)\}}{\mathbb{E}_\rho[\exp\{\phi(\tilde{s})^\top W f(\phi(s_t), a_t)\}]}$$
 predict reward & future state

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Value prediction network (VPN): $\phi(s_t), a_{t:t+k} \rightarrow r_{t+k}, V_{t+k}$ predict future reward & value function

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Temporal contrastive learning (TCL): $-\phi(s_{t+1})^\top W \phi(s_t) + \log \mathbb{E}_\rho[\exp\{\phi(\tilde{s})^\top W \phi(s_t)\}]$

Attentive contrastive learning (ACL): BERT-style contrastive learning of $\phi(s_t)$
contrast two state representations

- Carles Gelada, et al., Deepmdp: Learning continuous latent space models for representation learning. In International Conference on Machine Learning, pages 2170–2179. PMLR, 2019.
- Adam Stooke, Kimin Lee, Pieter Abbeel, and Michael Laskin. Decoupling representation learning from reinforcement learning, 2020.
- Amy Zhang, et al., Learning invariant representations for reinforcement learning without reconstruction. arXiv preprint arXiv:2006.10742, 2020.
- Junhyuk Oh, Satinder Singh, and Honglak Lee. Value prediction network. arXiv preprint arXiv:1707.03497, 2017.
- Deepak Pathak, et al., Curiosity-driven exploration by self-supervised prediction. In International Conference on Machine Learning, pages 2778–2787. PMLR, 2017.
- Evan Shelhamer, et. al., Loss is its own reward: Self-supervision for reinforcement learning. CoRR, abs/1612.07307, 2016. URL <http://arxiv.org/abs/1612.07307>.

Task Setups

Imitation

Choose domain $\in \{\text{halfcheetah}, \text{hopper}, \text{walker2d}, \text{ant}\}$
Choose data $\in \{\text{medium}, \text{medium-replay}\}$
Choose $N \in \{10000, 25000\}$

\rightarrow

Offline dataset: $\{\text{domain}\}-\{\text{data}\}-\text{v}0$
Downstream task: Behavioral cloning (BC) on first N
transitions from $\{\text{domain}\}\text{-expert-v}0$

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Offline RL

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Choose data $\in \{\text{expert}, \text{medium-expert}, \text{medium},$
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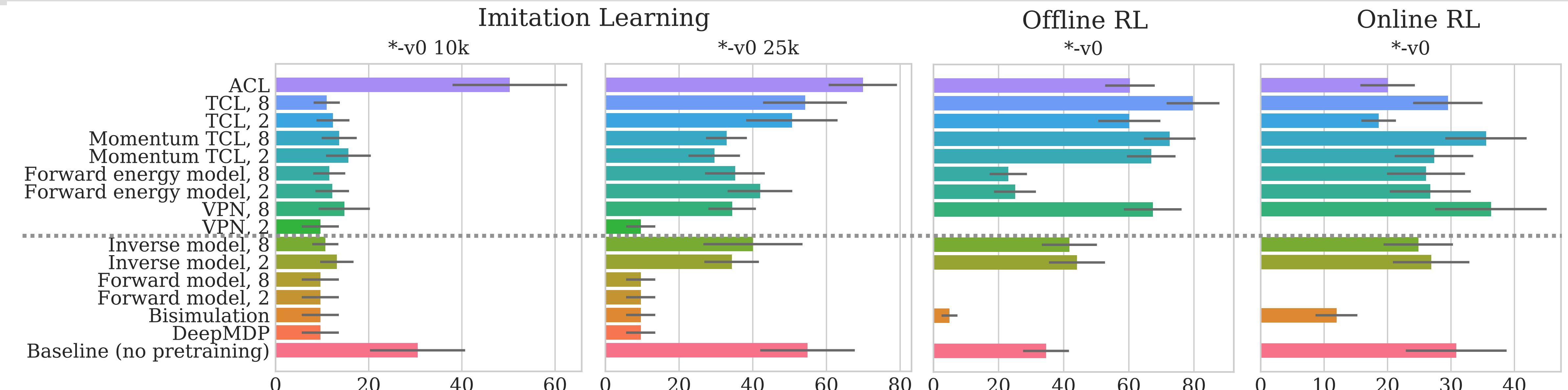
Online RL

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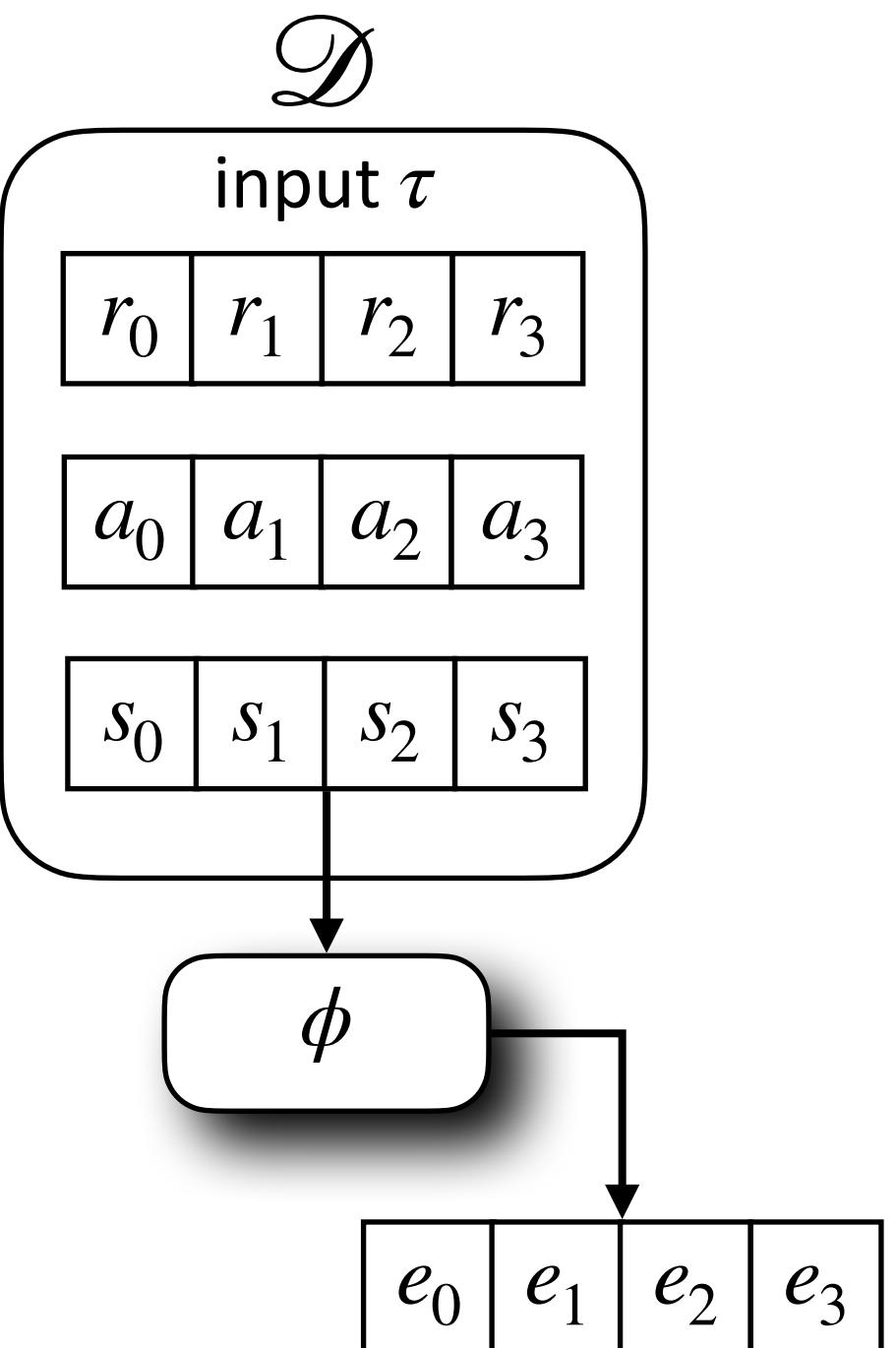
Offline dataset: $\{\text{domain}\}-\{\text{data}\}-v0$ with random masking
Downstream task: Soft actor critic (SAC) on randomly masked version of $\{\text{domain}\}$

Breadth Study

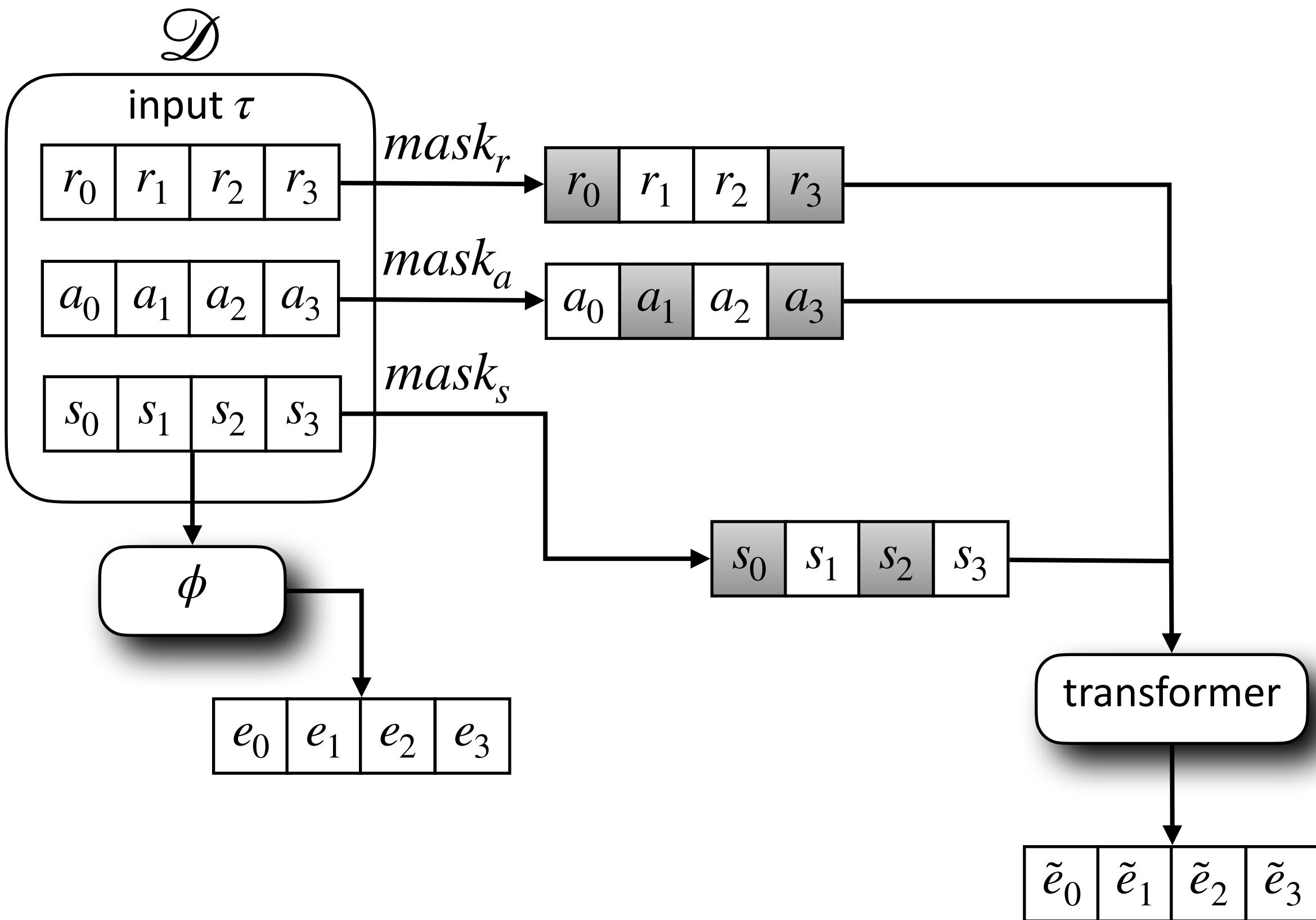


- Representation learning on average improves imitation learning, offline RL, and online RL tasks by 1.5x, 2.5x, and 15%
- Forward models of future representations (e.g., DeepMDP, Bisimulation) exhibit poor performance
- Contrastive self-prediction (e.g., ACL, TCL, VPN) works the best
- What is important in representation learning? Reward/action prediction? Direction of prediction? Momentum?

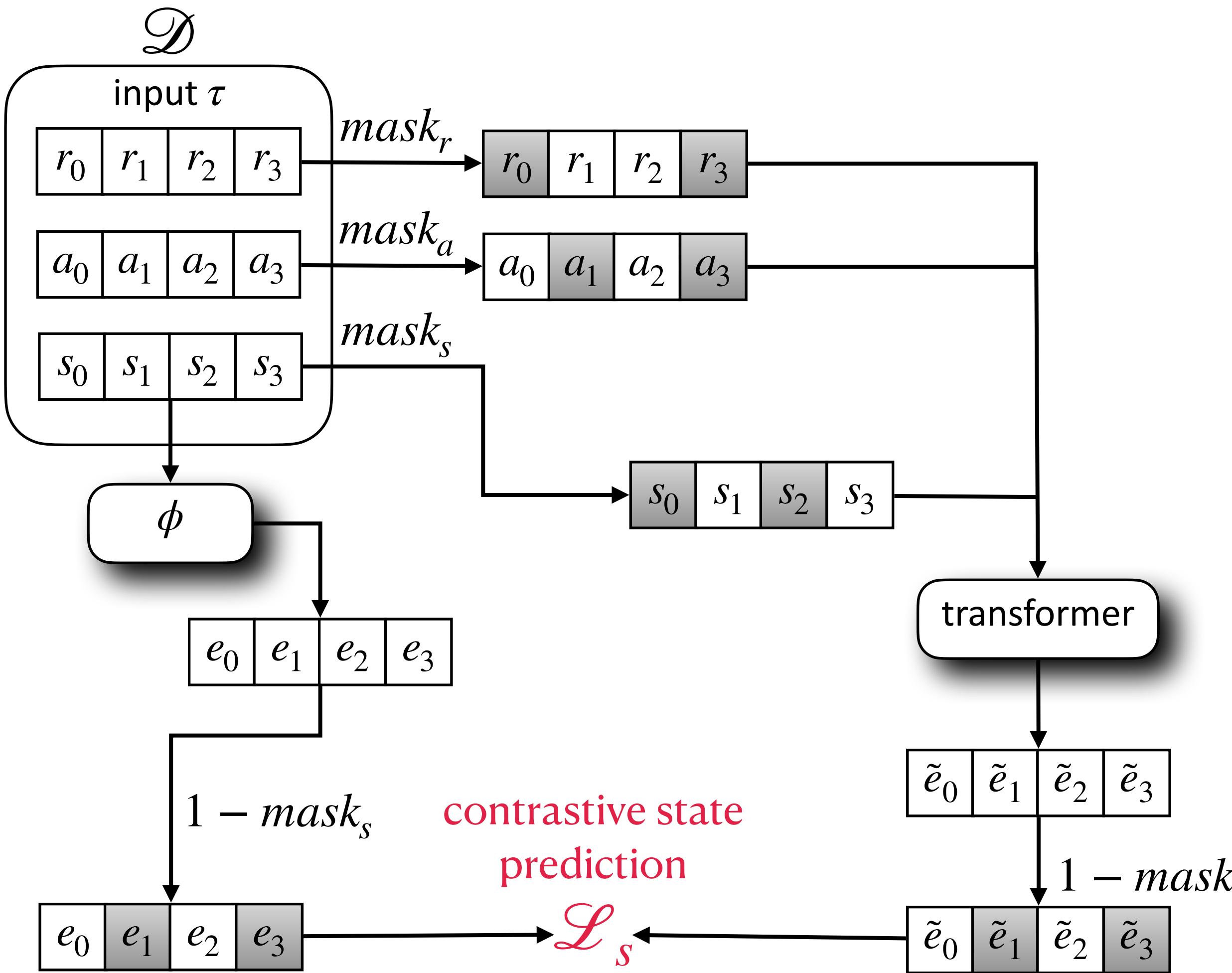
Attentive Contrastive Learning (ACL)



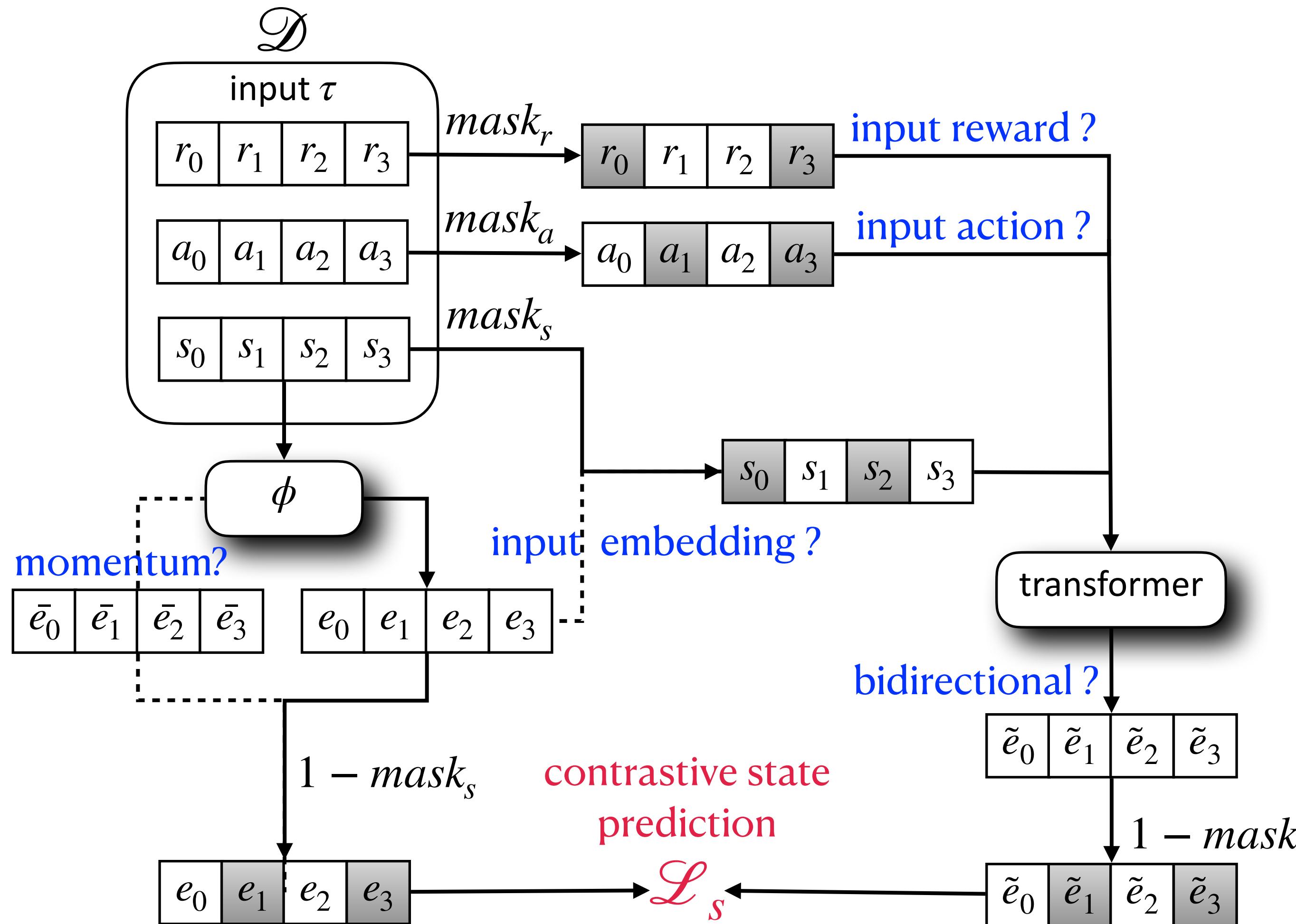
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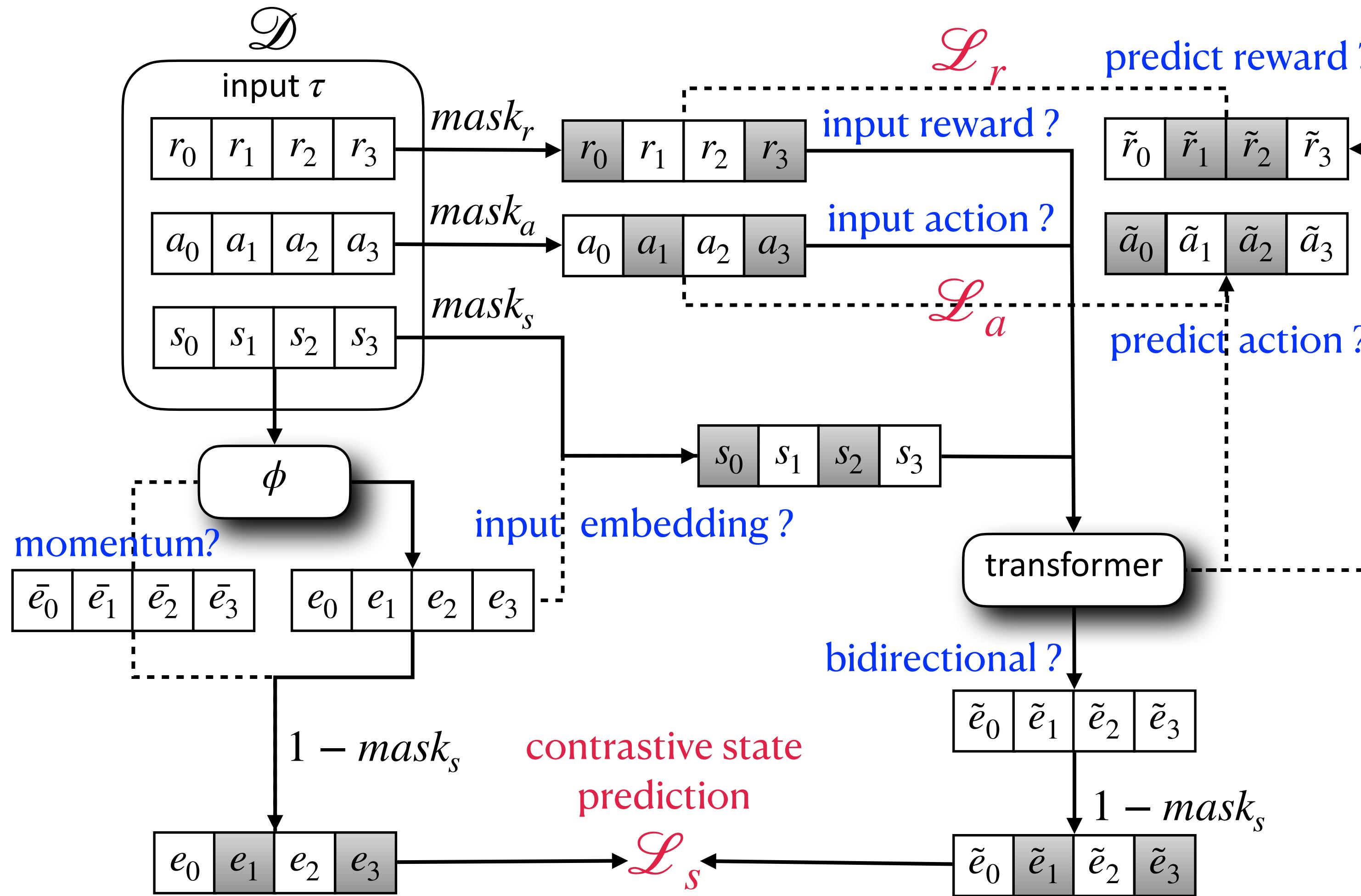
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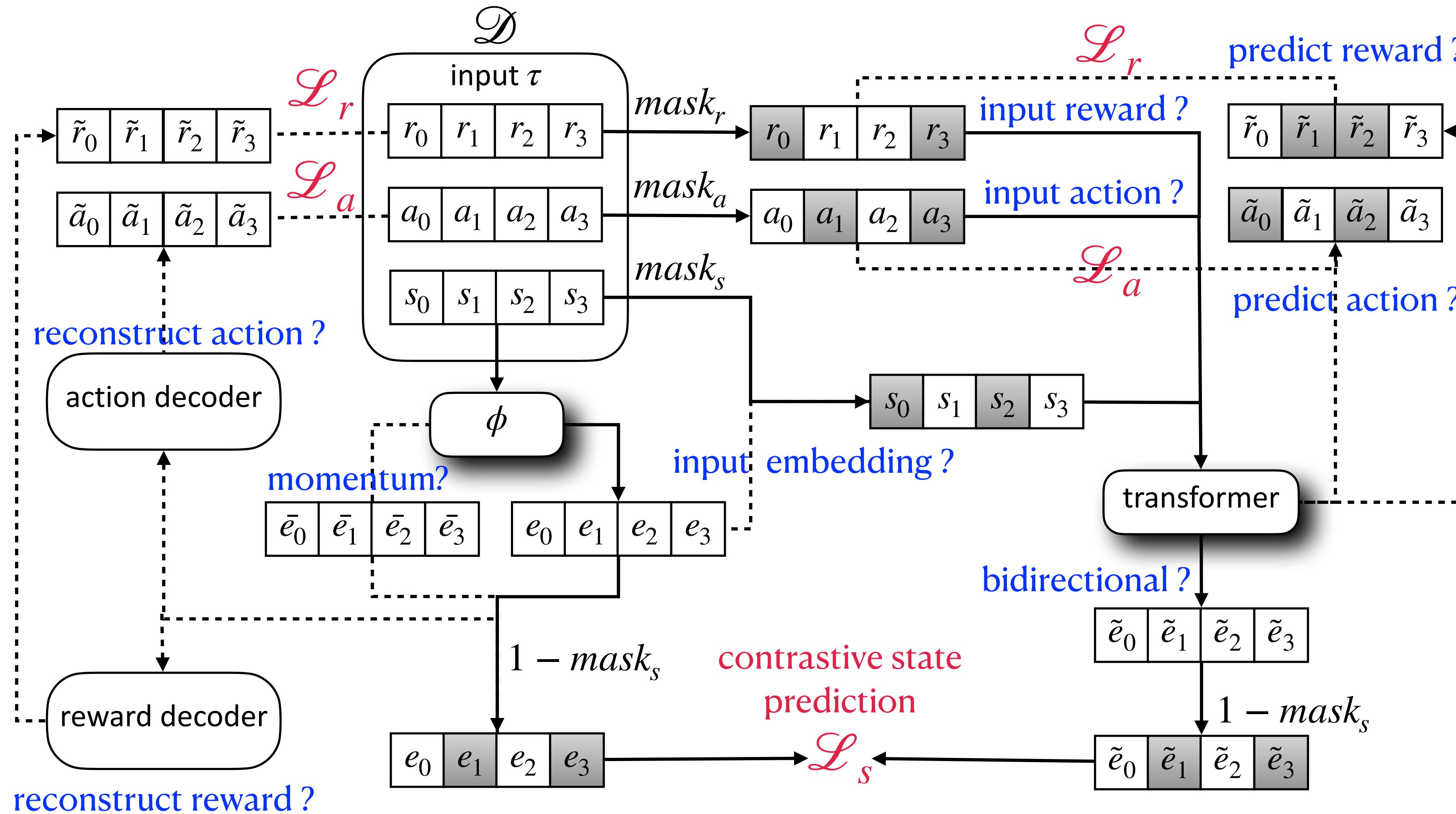
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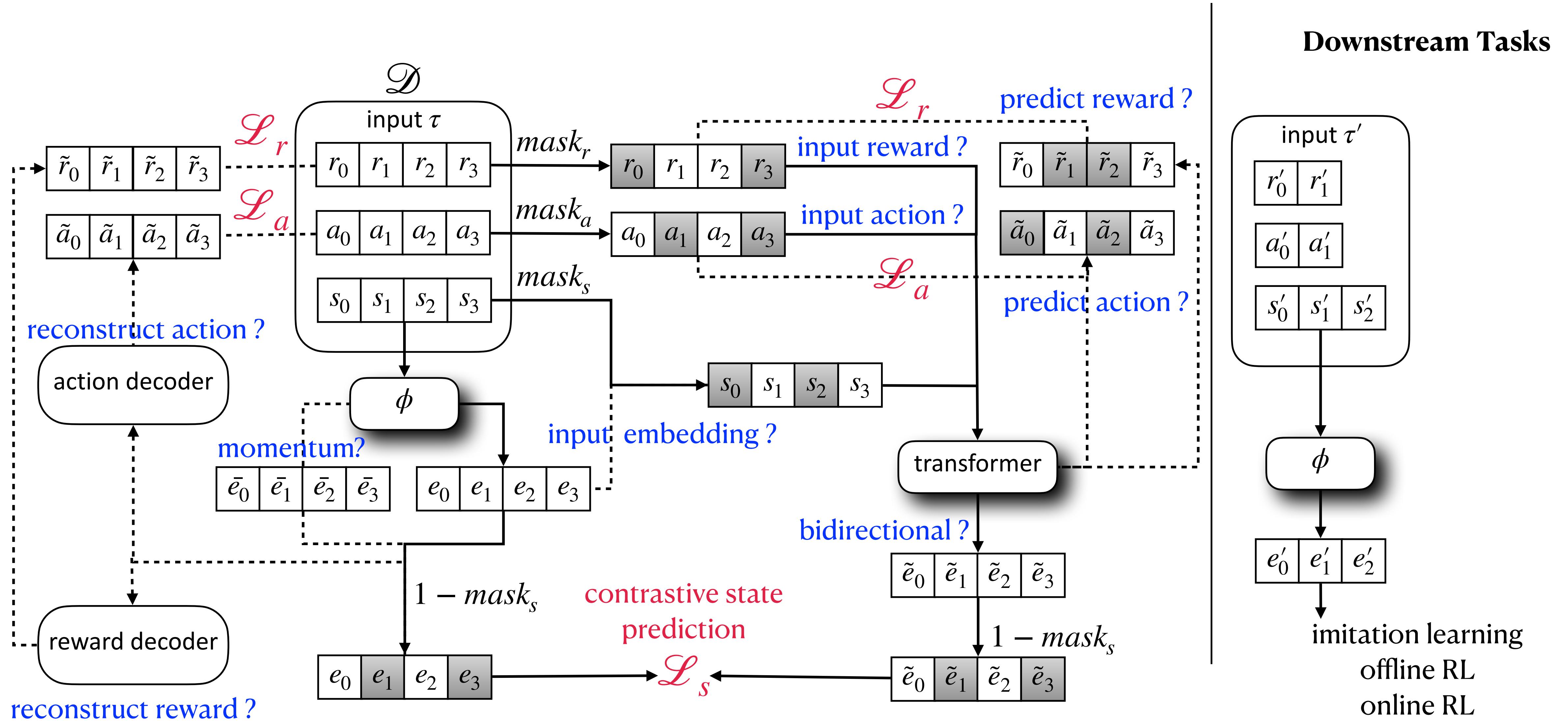
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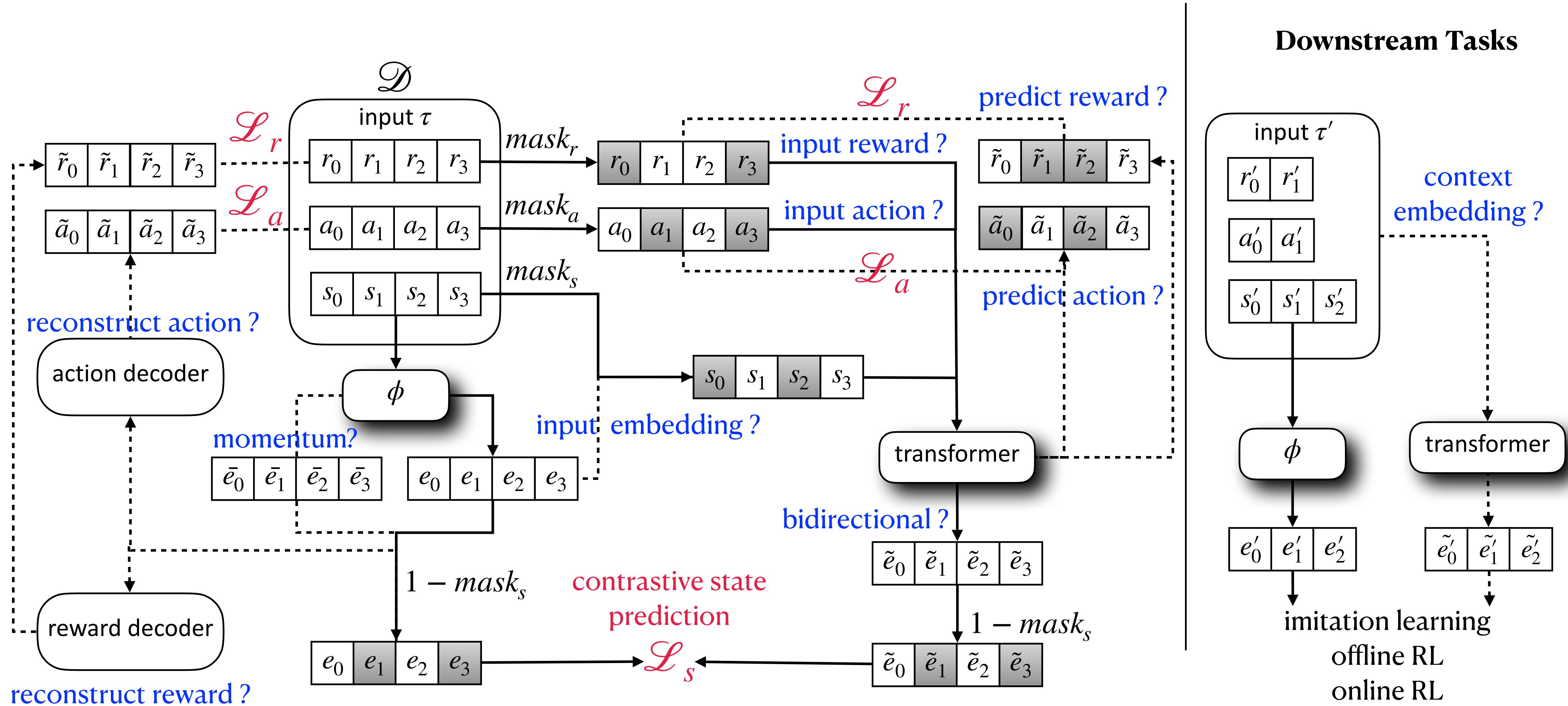
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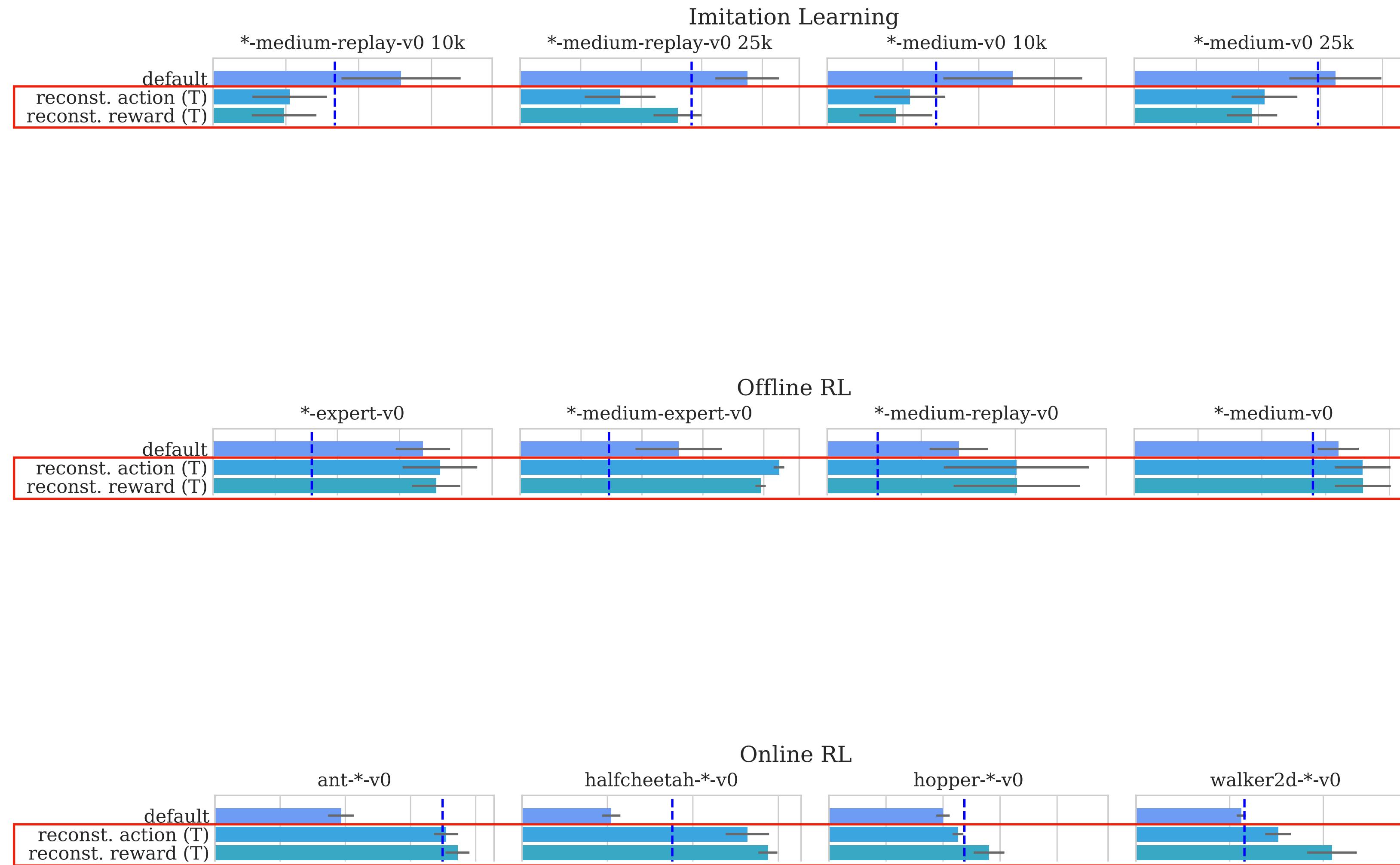
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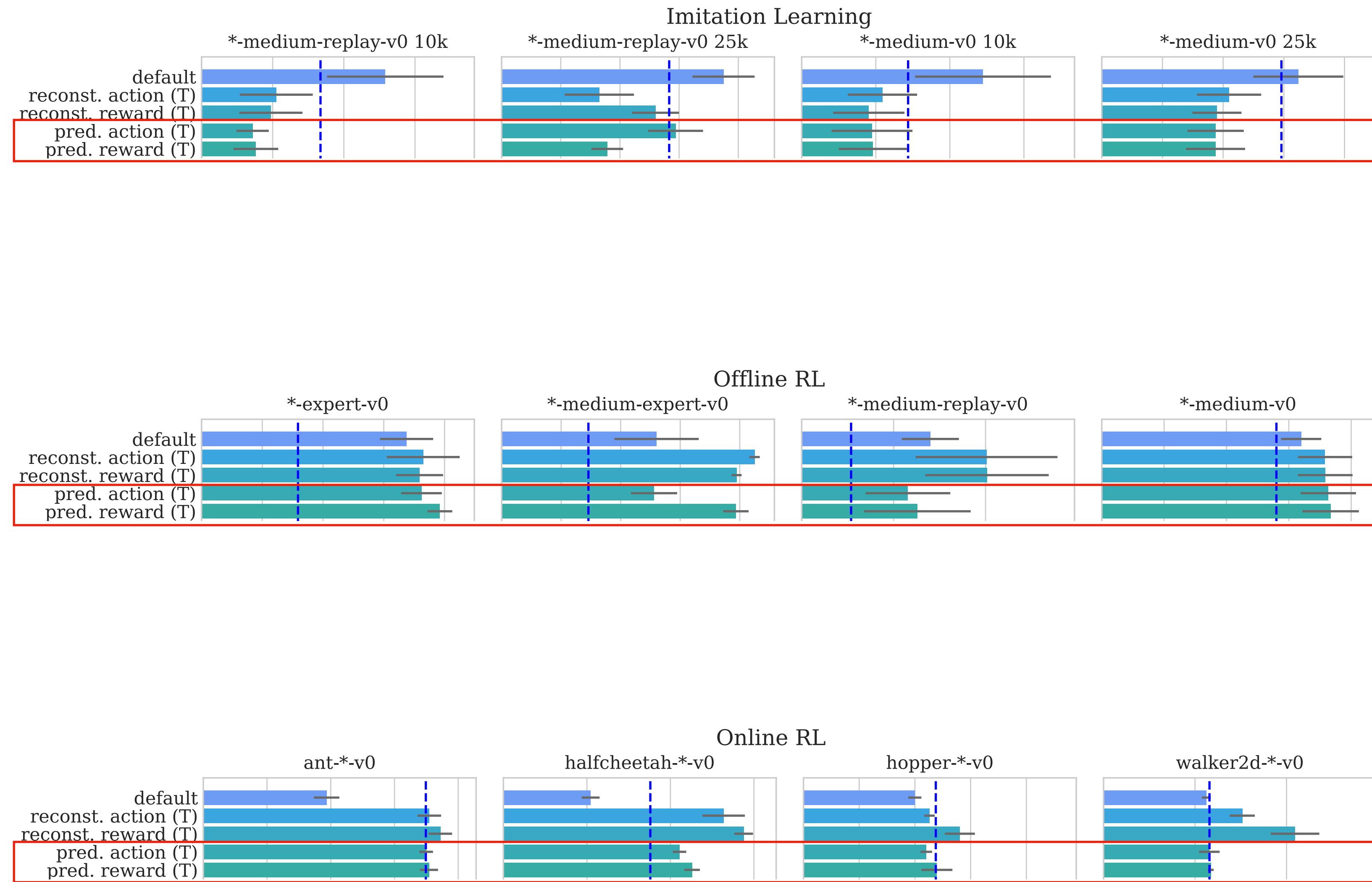
Depth Study on ACL



Depth Study on ACL

Factor	Description	Imitation	Offline	Online
reconstruct action	Add action prediction loss based on $\phi(s)$.	↓	↑	↑
reconstruct reward	Add a reward prediction loss based on $\phi(s)$.	↓	↑	↑

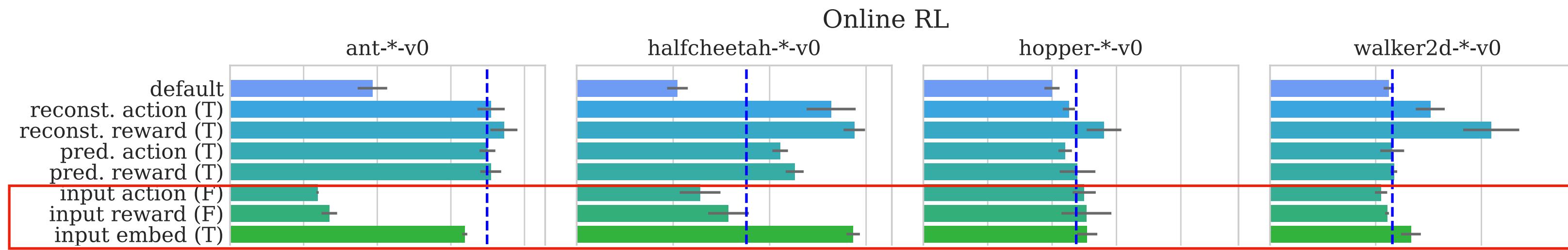
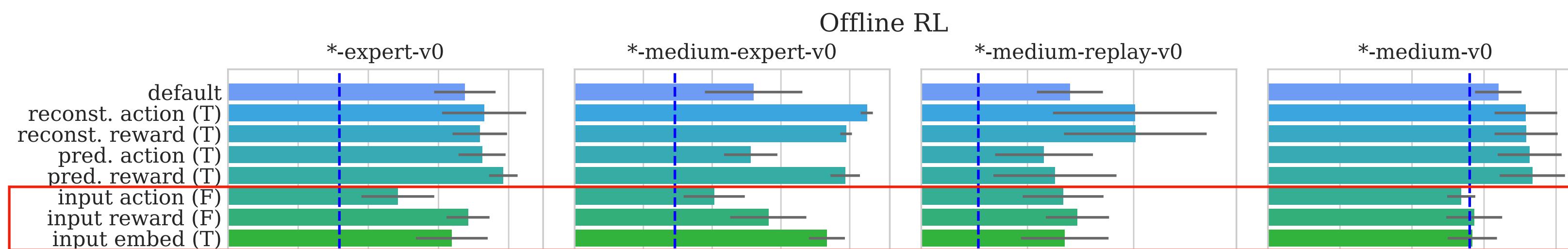
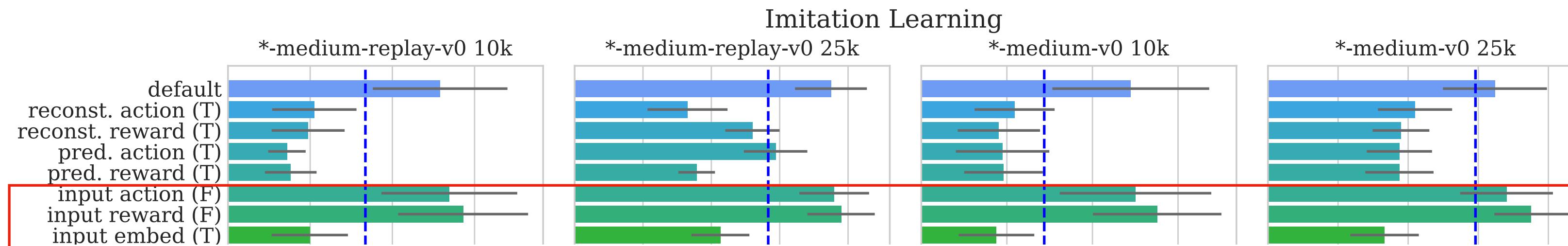
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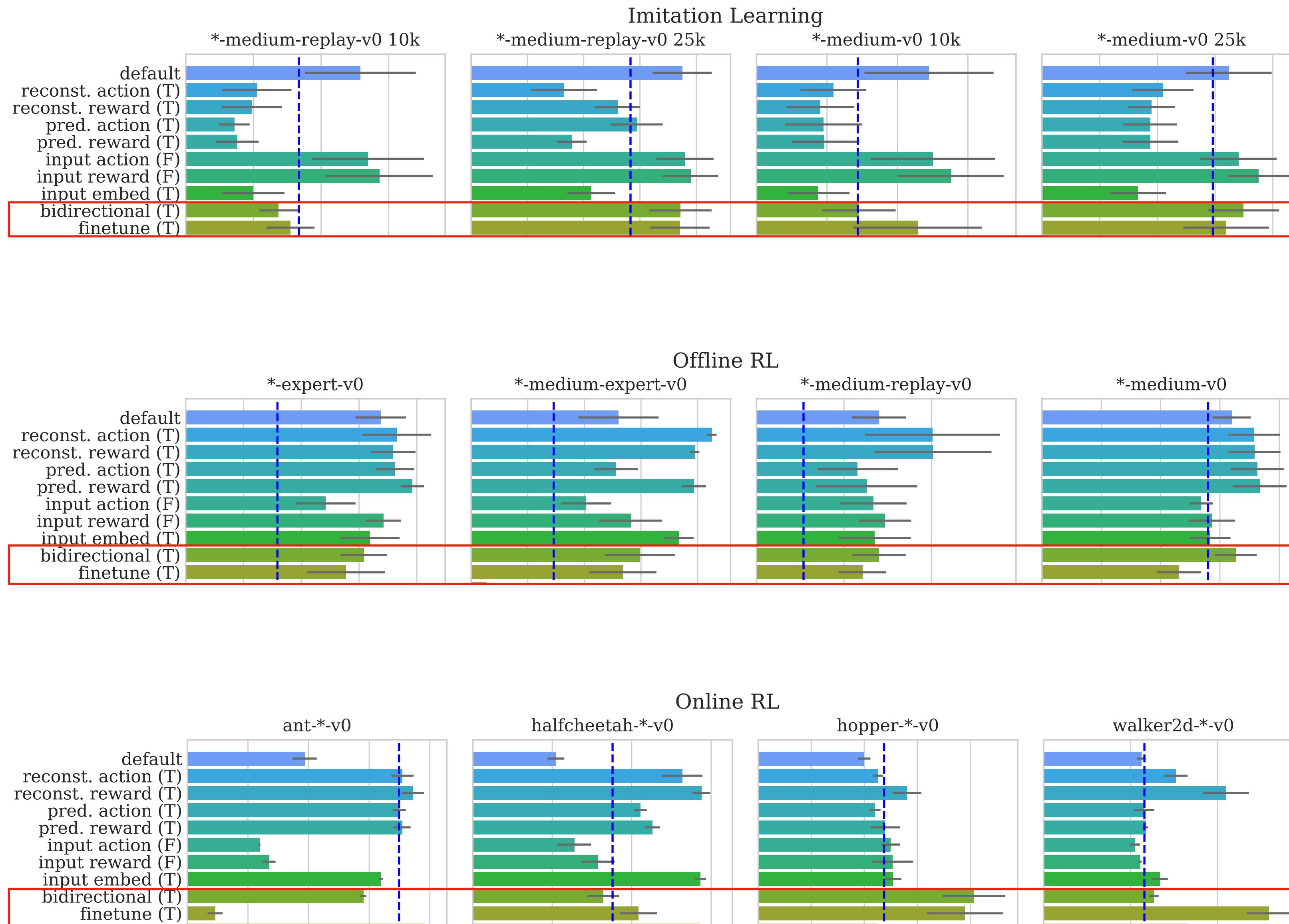
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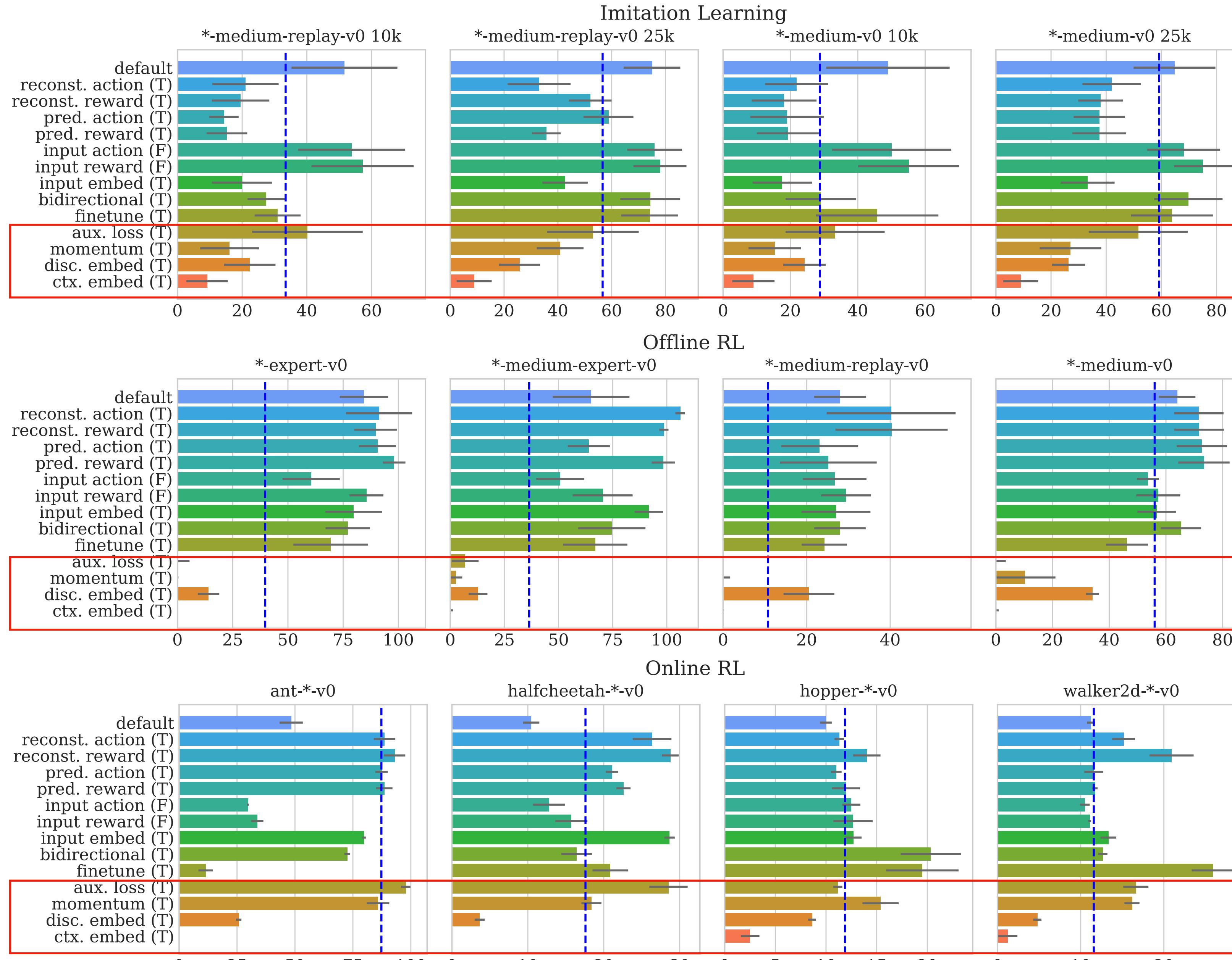
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bidirectional	To generate sequence output at position i , use full input sequence as opposed to only inputs at position $\leq i$.	↓	=	↑
finetune	Pass gradients into ϕ during learning on downstream tasks.	↓	↓	↑

Depth Study on ACL



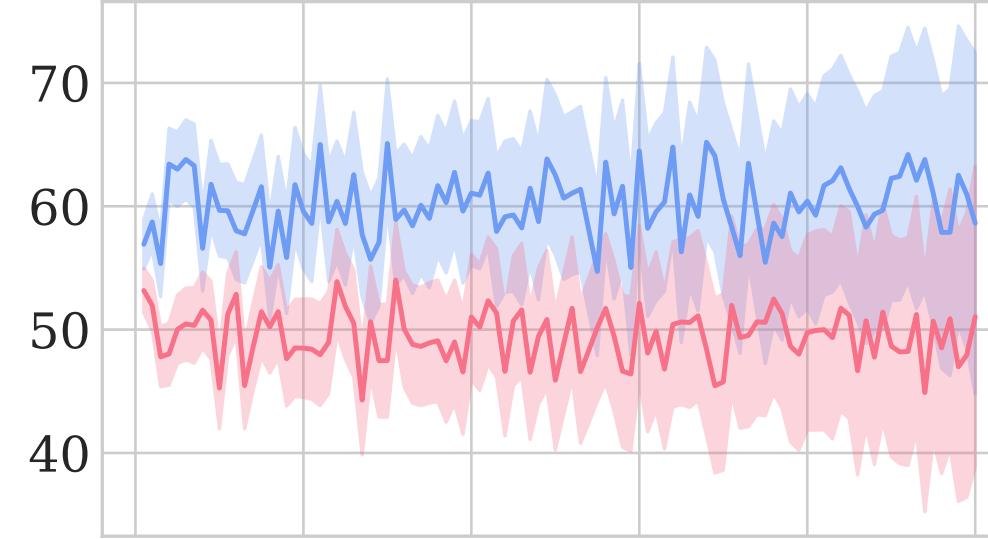
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finetune	Pass gradients into ϕ during learning on downstream tasks.	↓	↓	↑
auxiliary loss	Use representation learning objective as an auxiliary loss during downstream learning, as opposed to pretraining.	↓	↓	↑
momentum	Adopt an additional momentum representation network. Whenever this is true, we also set ‘input embed’ to true.	↓	↓	↑
discrete embedding	Learn discrete representations. Following Hafner et al. (2020), we treat the 256-dim output of ϕ as logits to sample 16 categorical distributions of dimension 16 each and use straight-through gradients.	↓	↓	↓
context embedding	Following Devlin et al. (2018), use transformer output as representations for downstream tasks. Whenever this is true, we also set ‘input embed’ to true.	↓	↓	↓

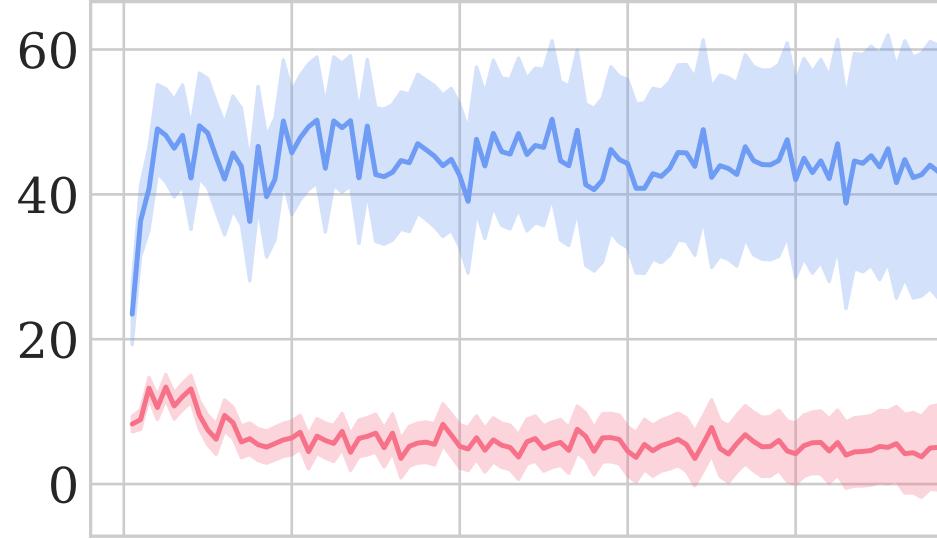
Best ACL Configuration

contrastive self-prediction no pretraining

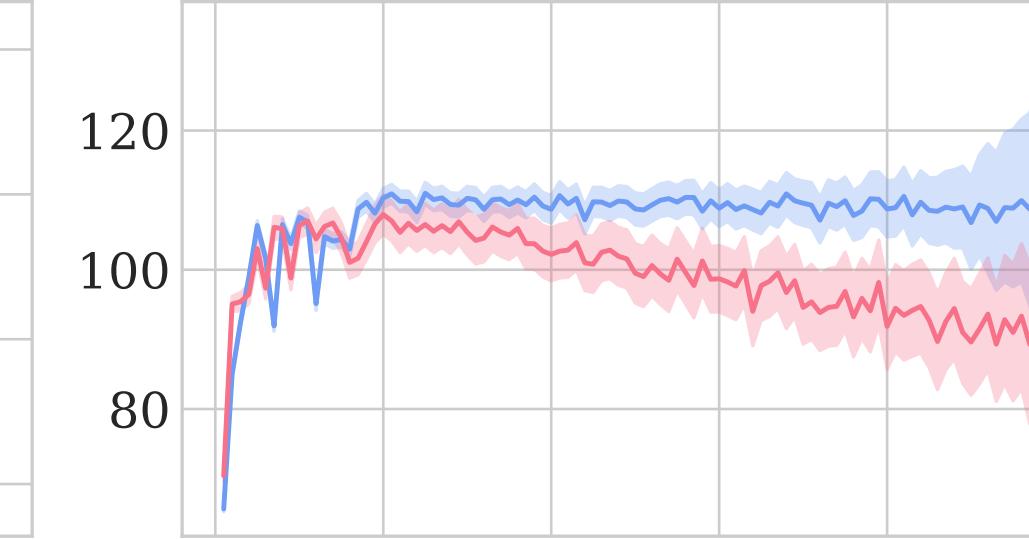
Imitation ant



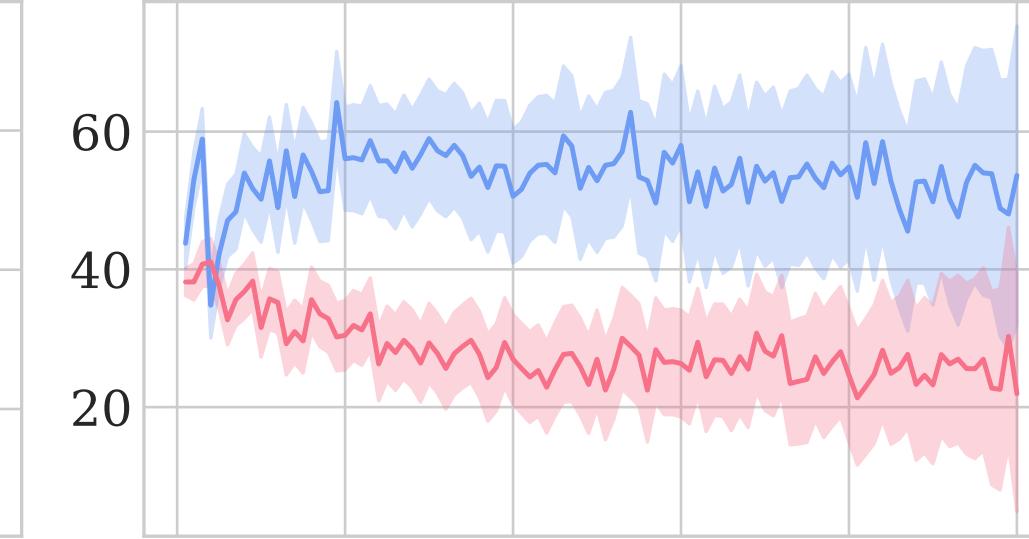
Imitation halfcheetah



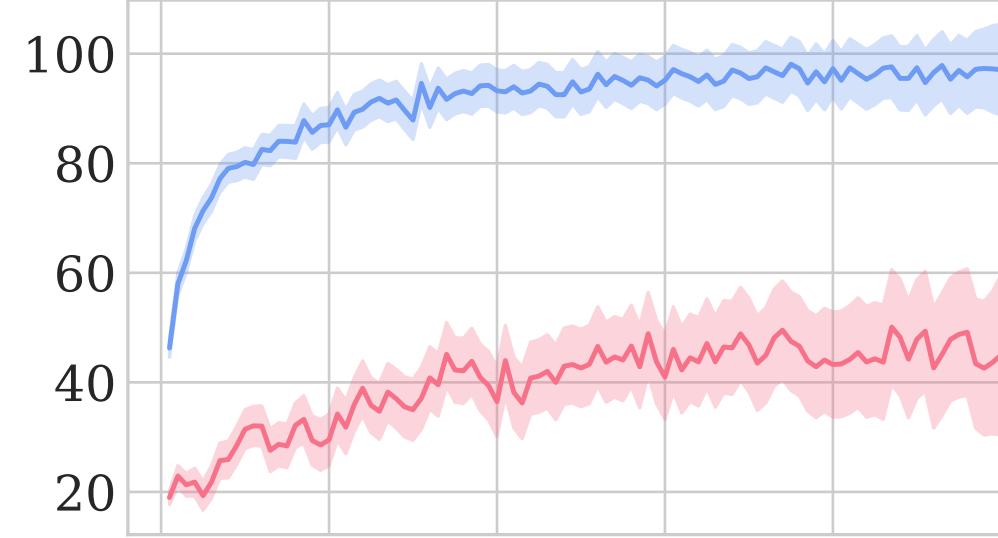
Imitation hopper



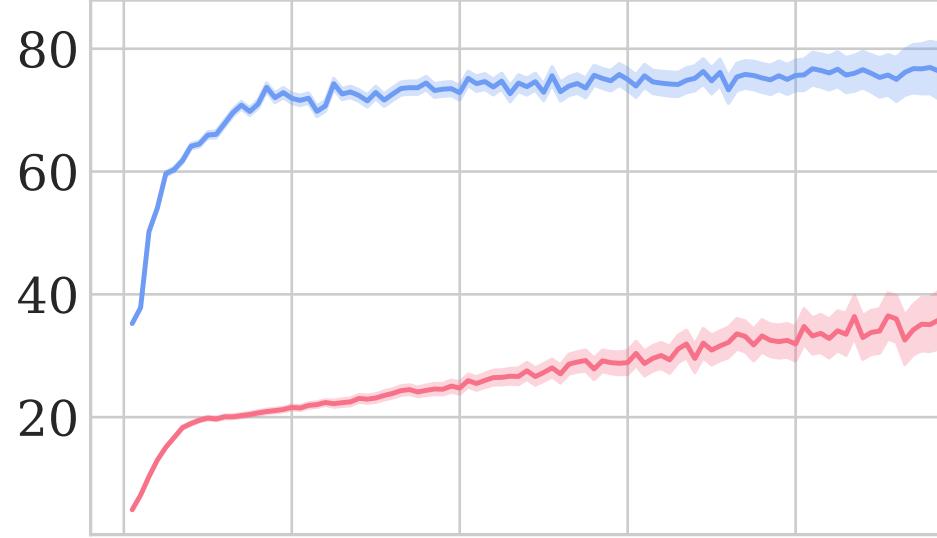
Imitation walker2d



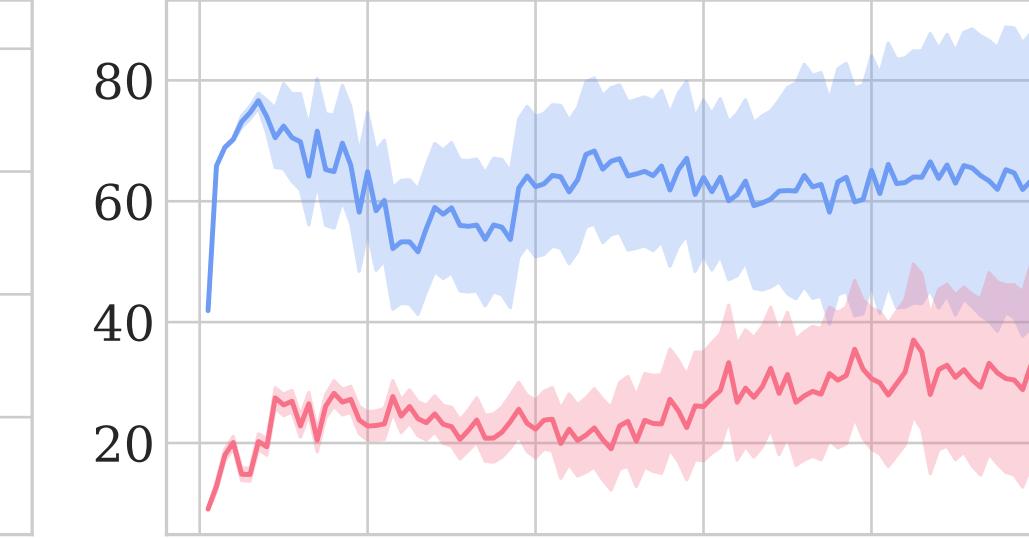
Offline ant



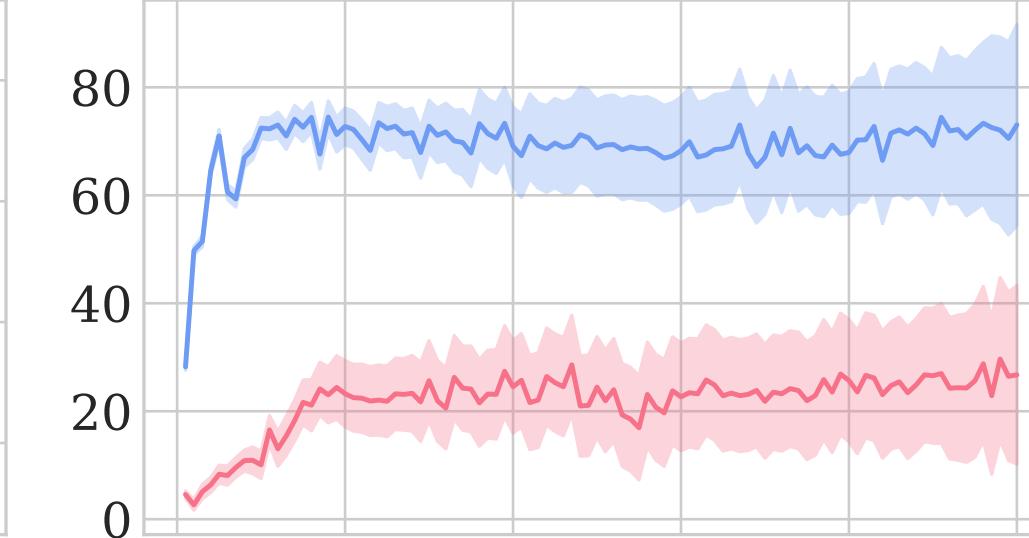
Offline halfcheetah



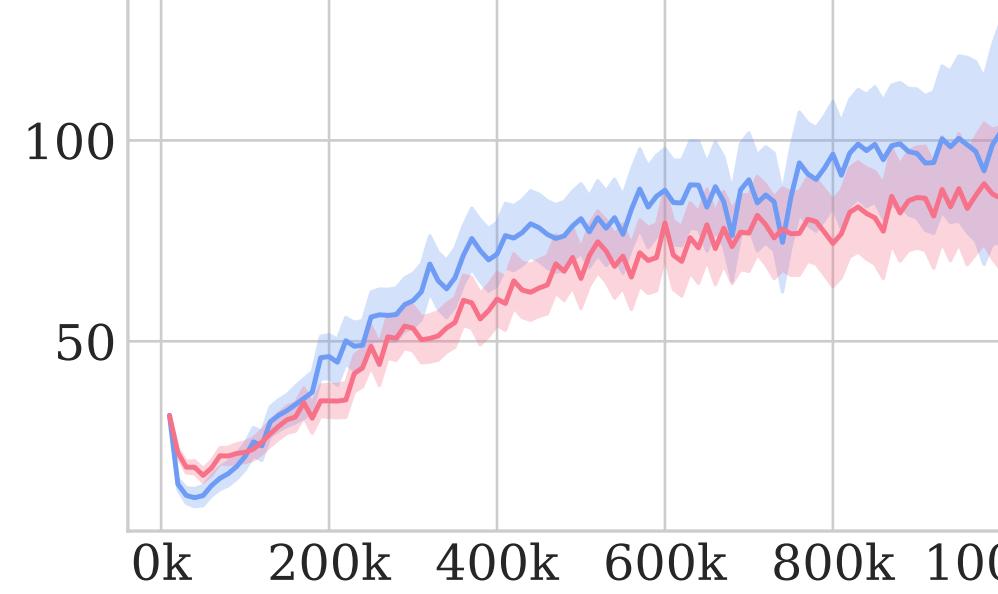
Offline hopper



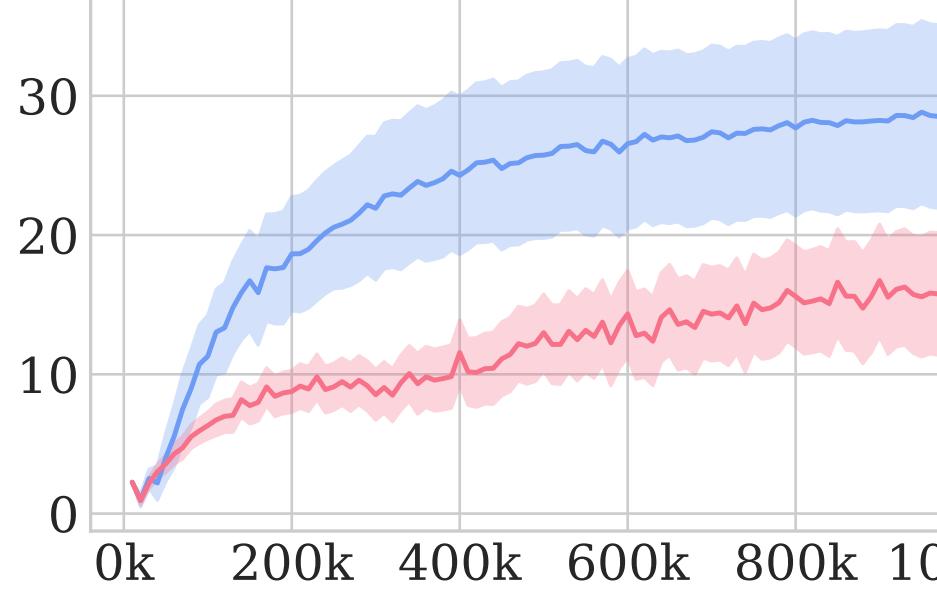
Offline walker2d



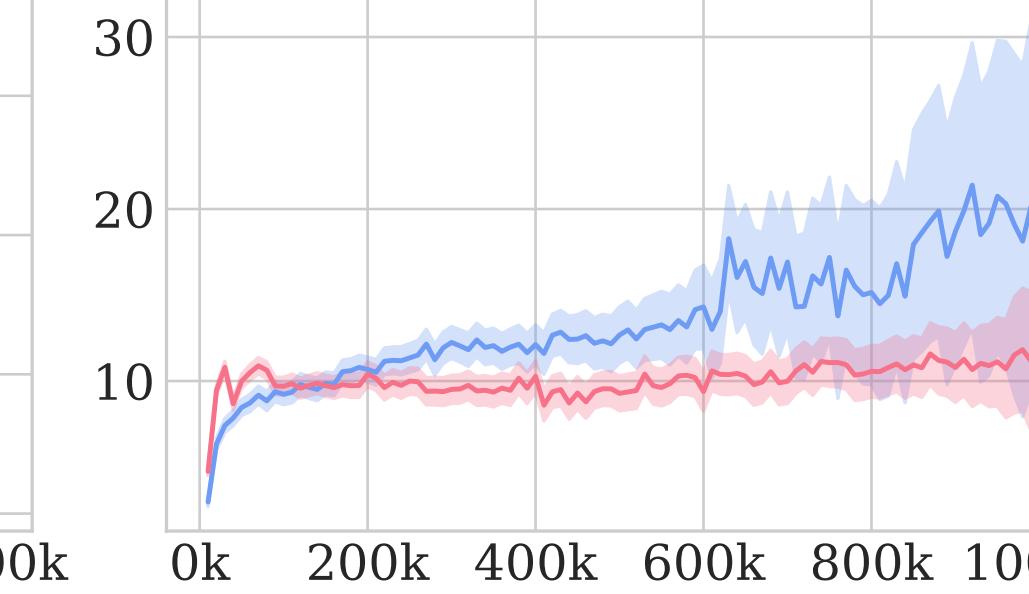
Online ant



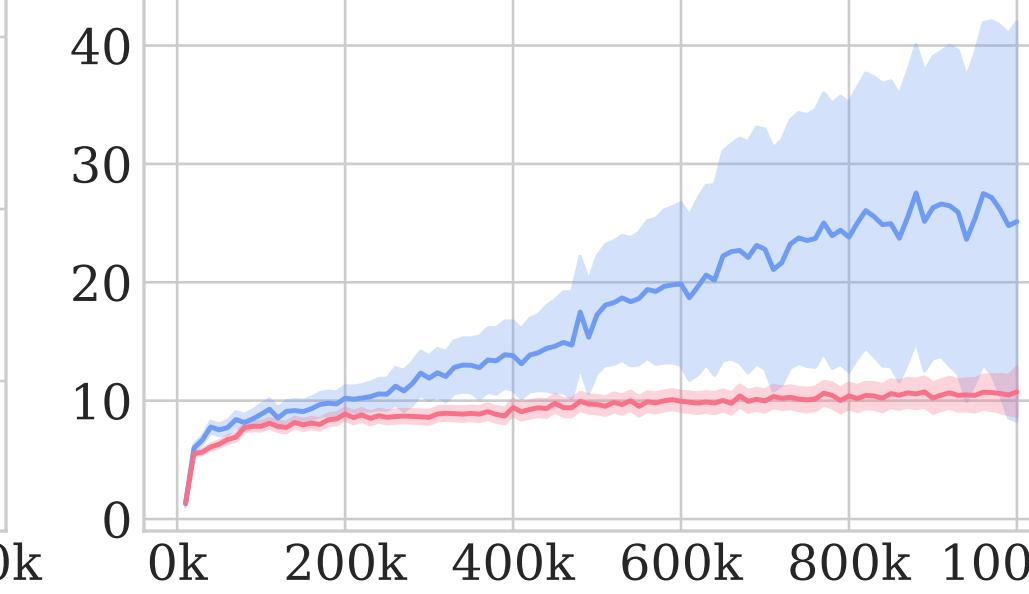
Online halfcheetah



Online hopper



Online walker2d



Future Directions

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- Other ways to apply transformer in offline RL
- Theoretical guarantees for representation learning in offline RL
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Questions?