

In [277...]

```
import os
import math
import pickle
import numpy as np
import pandas as pd
from tqdm import tqdm
import plotly.io as pio
import plotly.express as px
import plotly.graph_objects as go
from collections import defaultdict
from plotly.subplots import make_subplots
from concurrent.futures import ProcessPoolExecutor as Pool
from tensorboard.backend.event_processing.event_accumulator import EventAccumulator
pio.kaleido.scope.mathjax = None
pd.options.display.max_rows = None
```

In [277...]

```
LOGDIR = "logs"
ALGOS = ["bc", "bcq", "cql", "icq", "omar", "omiga", "madice", "madice-twolayer"]
# ALGOS = ["madice"]
SEEDS = [0, 1, 2, 3, 4]
SMACV1_ENV_NAMES = ["2c_vs_64zg", "5m_vs_6m", "6h_vs_8z", "corridor"]
SMACV2_ENV_NAMES = ["protoss", "terran", "zerg"]
MAMUJOCO_ENV_NAMES = ["Hopper-v2", "Ant-v2", "HalfCheetah-v2"]
SMACV1_MODES = ["poor", "medium", "good"]
SMACV2_MODES = ["5_vs_5", "10_vs_10", "10_vs_11", "20_vs_20", "20_vs_23"]
MAMUJOCO_MODES = ["expert", "medium", "medium-replay", "medium-expert"]

colors = px.colors.qualitative.Plotly
COLOR_MAPS = {
    "omiga": colors[0],
    "madice": colors[1],
    "madice-twolayer": "#ef823b",
    "icq": colors[2],
    "cql": colors[5],
    "bcq": "#4ba5ff",
    "bc": "#feb406",
    "omar": "#d366ff",
}
os.makedirs("graphs", exist_ok=True)
```

In [277...]

COLOR_MAPS

Out[277...]

```
{'omiga': '#636EFA',
'madice': '#EF553B',
'madice-twolayer': '#ef823b',
'icq': '#00CC96',
'cql': '#19D3F3',
'bcq': '#4ba5ff',
'bc': '#feb406',
'omar': '#d366ff'}
```

In [277...]

```
def listdir(path):
    if not os.path.exists(path):
        return []
    return sorted(os.listdir(path))
```

In [277...]

```
def read_tensorboard(logdir):
    files = listdir(logdir)
    if len(files) == 0:
        return {}
    path = f'{logdir}/{files[0]}'
    tb = EventAccumulator(path)
    tb.Reload()
    data = {}
    for tag in ["return", "winrate"]:
        if f"game/{tag}" in tb.Tags()["scalars"]:
            for item in tb.Scalars(f"game/{tag}"):
                if item.step not in data:
                    data[item.step] = {}
                data[item.step][tag] = item.value
    return data
```

In [277...]

```
def create_tasks(algo, env_name, mode):
    for seed in listdir(f"{LOGDIR}/{algo}/{env_name}/{mode}"):
        for alpha in listdir(f"{LOGDIR}/{algo}/{env_name}/{mode}/{seed}"):
            for f_func in listdir(f"{LOGDIR}/{algo}/{env_name}/{mode}/{seed}/{alpha}"):
                logdir = f"{LOGDIR}/{algo}/{env_name}/{mode}/{seed}/{alpha}/{f_func}"
                yield logdir, alpha, f_func
```

In [277...]

```
def create_smacv1_tasks(p):
    tasks = []
    for algo in ALGOS:
        for env_name in SMACV1_ENV_NAMES:
            for mode in SMACV1_MODES:
                for logdir, alpha, f_func in create_tasks(algo, env_name, mode):
                    tasks.append((p.submit(read_tensorboard, logdir), env_name, mode, algo, alpha, f_func))
    return tasks
```

In [277...]

```
def create_smacv2_tasks(p):
    tasks = []
    for algo in ALGOS:
        for env_name in SMACV2_ENV_NAMES:
            for mode in SMACV2_MODES:
                for logdir, alpha, f_func in create_tasks(algo, env_name, mode):
                    tasks.append((p.submit(read_tensorboard, logdir), env_name, mode, algo, alpha, f_func))
    return tasks
```

In [277...]

```
def create_mamujoco_tasks(p):
    tasks = []
    for algo in ALGOS:
        for env_name in MAMUJOCO_ENV_NAMES:
            for mode in MAMUJOCO_MODES:
                for logdir, alpha, f_func in create_tasks(algo, env_name, mode):
                    tasks.append((p.submit(read_tensorboard, logdir), env_name, mode, algo, alpha, f_func))
    return tasks
```

```
In [278...]  
results = {}  
with Pool() as p:  
    tasks = []  
    tasks += create_smacv1_tasks(p)  
    tasks += create_smacv2_tasks(p)  
    tasks += create_mamujoco_tasks(p)  
  
    for task, env_name, mode, algo, alpha, f_func in tqdm(tasks):  
        data = task.result()  
        if len(data) == 0:  
            continue  
        color = COLOR_MAPS[algo]  
        if algo == "madice":  
            algo = "ComaDICE (ours)"  
        elif algo == "madice-twolayer":  
            algo = "ComaDICE (2-layer)"  
        else:  
            algo = algo.upper()  
        COLOR_MAPS[algo] = color  
        if (env_name, mode) not in results:  
            results[(env_name, mode)] = {}  
        if (algo, alpha, f_func) not in results[(env_name, mode)]:  
            results[(env_name, mode)][(algo, alpha, f_func)] = []  
        results[(env_name, mode)][(algo, alpha, f_func)].append(data)
```

```
100%|██████████| 2730/2730 [00:00<00:00, 480142.99it/s]
```

```
In [278...]  
os.makedirs("saved_results", exist_ok=True)  
with open("saved_results/log_data.pkl", "wb") as f:  
    pickle.dump(data, f)
```

```
In [278...]  
main_results = {}  
for (env_name, mode), data in results.items():  
    for (algo, alpha, f_func), items in data.items():  
        if alpha != "alpha10" or f_func != "soft_chisquare":  
            continue  
        if "2-layer" in algo:  
            continue  
        if (env_name, mode) not in main_results:  
            main_results[(env_name, mode)] = {}  
        main_results[(env_name, mode)][algo] = items
```

```
In [278...]  
ablation_results = {}  
for (env_name, mode), data in results.items():  
    for (algo, alpha, f_func), items in data.items():  
        if algo != "ComaDICE (ours)":  
            continue  
        if (env_name, mode) not in ablation_results:  
            ablation_results[(env_name, mode)] = {}  
        ablation_results[(env_name, mode)][(alpha, f_func)] = items
```

```
In [278...]  
ablation_mixer_results = {}  
for (env_name, mode), data in results.items():  
    for (algo, alpha, f_func), items in data.items():  
        if alpha != "alpha10" or f_func != "soft_chisquare":  
            continue  
        if "ComaDICE" not in algo:  
            continue  
        if (env_name, mode) not in ablation_mixer_results:  
            ablation_mixer_results[(env_name, mode)] = {}  
        ablation_mixer_results[(env_name, mode)][algo] = items
```

```
In [278...]  
def analyze(items, tag="return"):  
    if not isinstance(items, list):  
        return np.nan  
    items = [item[max(item.keys())] for item in items]  
    items = [item[tag] for item in items if tag in item]  
    if len(items) == 0:  
        return np.nan  
    mean = np.mean(items)  
    std = np.std(items)  
    if tag == "winrate":  
        return f"{mean:.2f}±{std*100:.2f}"  
    else:  
        return f"{mean:.2f}±{std:.2f}"
```

```
In [278...]  
pd.DataFrame.from_dict(main_results).map(analyze, tag="return").T
```

Out[278...]

		BC	BCQ	CQL	ICQ	OMAR	OMIGA	ComaDICE (ours)
2c_vs_64zg	poor	11.56±0.39	12.46±0.18	10.83±0.51	12.56±0.18	11.33±0.50	13.02±0.66	12.15±0.51
	medium	13.37±1.87	15.58±0.37	12.82±1.61	15.57±0.61	10.20±0.20	16.03±0.19	16.30±0.66
	good	17.90±1.30	19.13±0.27	18.48±0.95	18.82±0.17	17.27±0.78	19.15±0.32	20.34±0.06
5m_vs_6m	poor	6.98±0.47	7.61±0.36	7.43±0.10	7.26±0.19	7.27±0.42	7.52±0.21	8.12±0.55
	medium	7.05±0.82	7.58±0.10	7.78±0.10	7.77±0.30	7.08±0.51	7.92±0.57	8.65±0.38
	good	6.95±0.47	7.76±0.15	8.08±0.21	7.87±0.30	7.40±0.63	8.25±0.37	8.66±0.50
6h_vs_8z	poor	8.57±0.81	10.84±0.16	10.81±0.52	10.55±0.10	10.63±0.25	11.31±0.19	11.37±0.58
	medium	9.46±0.35	11.77±0.16	11.29±0.29	11.13±0.33	10.36±0.16	12.19±0.22	12.83±0.22
	good	10.02±1.67	12.19±0.23	10.44±0.20	11.81±0.12	9.85±0.28	12.54±0.21	13.11±0.46
corridor	poor	2.91±0.57	4.47±0.94	4.08±0.60	4.47±0.33	4.28±0.49	5.61±0.35	6.36±0.47
	medium	7.39±0.79	10.82±0.92	7.04±0.66	11.30±1.57	7.26±0.71	11.66±1.30	12.90±0.62
	good	10.81±2.61	15.24±1.21	5.22±0.81	15.54±1.12	6.74±0.69	15.88±0.89	17.98±0.08
protoss	5_vs_5	13.24±0.68	6.84±1.61	9.31±1.64	10.72±1.16	8.89±0.83	14.32±1.37	14.41±1.15
	10_vs_10	12.00±1.91	7.72±1.32	11.27±0.92	10.42±1.57	8.76±0.57	14.23±1.48	14.55±1.81
	10_vs_11	11.17±0.53	5.18±1.43	7.95±0.76	10.33±0.66	8.04±0.26	12.07±0.49	13.18±0.86
	20_vs_20	13.14±0.45	4.82±0.58	10.49±0.94	11.79±0.49	9.09±0.48	13.96±0.92	14.83±0.99
	20_vs_23	11.20±0.52	3.54±0.64	5.57±0.75	10.20±0.67	7.41±0.67	12.98±1.11	13.26±0.90
terran	5_vs_5	10.83±1.44	6.36±1.05	6.51±0.86	6.78±0.58	6.95±0.59	10.46±1.25	10.70±1.53
	10_vs_10	10.30±0.33	4.58±0.40	6.82±0.62	8.75±1.45	7.62±1.00	10.08±0.65	11.82±0.90
	10_vs_11	8.98±0.69	3.61±1.14	5.46±0.23	5.52±0.87	5.90±0.68	8.80±1.35	9.40±0.95
	20_vs_20	10.81±0.77	3.95±0.60	4.32±0.61	8.33±0.31	7.31±0.36	10.52±0.71	11.81±0.46
	20_vs_23	7.20±0.98	1.22±0.97	1.63±0.20	5.33±0.52	5.10±0.30	7.94±0.60	8.21±0.72
zerg	5_vs_5	10.49±2.22	6.57±0.22	6.68±0.52	6.54±0.89	7.75±0.90	8.89±1.09	10.68±1.96
	10_vs_10	10.96±0.78	7.27±1.05	7.19±0.29	7.74±1.14	7.49±0.81	11.81±1.60	11.46±0.95
	10_vs_11	9.23±1.11	7.60±0.87	6.73±0.45	6.79±0.95	6.48±0.96	9.51±1.19	11.01±0.94
	20_vs_20	9.28±0.47	3.69±0.40	4.69±0.26	6.89±0.49	6.92±0.84	9.16±0.50	9.42±1.16
	20_vs_23	8.54±0.73	3.28±0.30	4.15±0.63	6.95±0.46	5.67±0.42	9.81±0.58	10.51±0.79
Hopper-v2	expert	209.85±191.12	77.85±58.04	159.14±313.83	754.74±806.28	2.36±1.46	859.63±709.47	2827.70±62.91
	medium	511.95±7.43	44.58±20.62	401.27±199.88	501.79±14.03	21.34±24.90	1189.26±544.30	822.55±66.21
	medium-replay	133.31±53.54	26.53±24.04	31.37±15.16	195.39±103.61	3.30±3.22	774.18±494.27	906.25±242.13
	medium-expert	155.30±111.53	54.31±23.66	64.82±123.31	355.44±373.86	1.44±0.86	709.00±595.66	1362.44±522.87
Ant-v2	expert	2046.31±6.18	1317.73±286.28	1042.39±2021.64	2050.00±11.86	312.54±297.48	2055.46±1.58	2056.89±5.92
	medium	1421.09±7.88	1059.60±91.22	533.90±1766.43	1412.41±10.93	-1710.04±1588.98	1418.44±5.36	1425.00±2.87
	medium-replay	994.00±20.29	950.77±48.76	234.62±1618.25	1016.68±53.51	-2014.20±844.68	1105.13±88.87	1122.94±61.04
	medium-expert	1561.70±64.81	1020.89±242.74	800.22±1621.47	1590.18±85.61	-2992.80±6.95	1720.33±110.63	1813.88±68.37
HalfCheetah-v2	expert	3251.22±386.83	2992.71±629.65	1189.54±1034.49	2955.94±459.19	-206.73±161.12	3383.61±552.67	4082.93±45.68
	medium	2280.32±178.22	2590.47±1110.35	1011.35±1016.94	2549.27±96.34	-265.68±146.98	3608.13±237.37	2664.71±54.19
	medium-replay	1886.20±390.77	-333.64±152.06	1998.67±693.92	1922.42±612.87	-235.42±154.89	2504.70±83.47	2855.02±242.25
	medium-expert	2451.95±782.99	3543.70±780.89	1194.23±1081.05	2833.99±420.32	-253.84±63.94	2948.46±518.89	3889.74±81.64

In [278...]

pd.DataFrame.from_dict(ablation_results).map(analyze, tag="return").T

Out[278...]

		alpha0.01	alpha0.1	alpha1		alpha10	alpha100	
		soft_chisquare	soft_chisquare	soft_chisquare	chisquare	kl	soft_chisquare	soft_chisquare
2c_vs_64zg	poor	10.56±0.54	11.08±0.36	11.12±0.13	11.64±0.24	11.10±0.31	12.15±0.51	11.78±0.22
	medium	9.63±0.46	13.07±0.78	12.54±2.39	16.06±0.59	15.69±0.26	16.30±0.66	16.00±0.25
	good	11.05±1.39	9.58±2.67	17.43±0.50	19.74±0.10	19.30±0.06	20.34±0.06	19.91±0.07
5m_vs_6m	poor	5.71±0.11	5.06±0.26	7.08±0.71	7.78±0.37	7.49±0.49	8.12±0.55	7.67±0.29
	medium	5.60±0.14	5.29±0.16	7.77±0.77	8.09±0.46	7.74±0.39	8.65±0.38	8.47±0.67
	good	5.72±0.10	5.70±0.19	7.75±0.49	8.68±0.57	8.11±0.44	8.66±0.50	8.81±0.76
6h_vs_8z	poor	8.54±0.24	9.60±0.28	10.00±0.33	10.54±0.26	10.00±0.20	11.37±0.58	10.69±0.36
	medium	8.54±0.59	10.47±0.80	10.75±0.49	12.87±0.37	12.43±0.48	12.83±0.22	12.27±0.32
	good	7.87±0.11	9.50±0.55	11.34±0.56	12.70±0.38	12.42±0.47	13.11±0.46	12.76±0.45
corridor	poor	2.07±0.43	3.73±0.96	6.09±0.83	6.47±0.49	6.09±0.43	6.36±0.47	4.97±1.06
	medium	1.68±1.03	2.22±1.66	11.34±0.29	12.67±0.73	11.98±0.67	12.90±0.62	13.34±0.13
	good	4.74±2.39	3.82±4.99	15.66±0.29	17.34±0.13	16.90±0.10	17.98±0.08	17.42±0.13
protoss	5_vs_5	12.21±1.05	13.08±1.28	13.22±1.06	14.63±0.54	13.55±0.94	14.41±1.15	14.04±2.02
	10_vs_10	12.85±0.89	13.98±0.84	13.44±1.19	14.70±1.30	13.69±1.60	14.55±1.81	14.12±1.30
	10_vs_11	9.89±1.09	11.14±0.78	11.29±1.20	12.79±1.04	11.42±1.72	13.18±0.86	12.17±1.07
	20_vs_20	10.25±0.53	11.12±1.02	12.22±0.85	12.72±0.29	13.14±0.74	14.83±0.99	13.19±0.40
	20_vs_23	7.98±2.32	11.22±1.22	11.70±0.56	12.44±0.94	12.48±0.74	13.26±0.90	13.17±0.51
terran	5_vs_5	11.06±1.83	10.09±1.16	9.01±0.98	11.12±1.22	12.71±2.01	10.70±1.53	12.61±1.94
	10_vs_10	8.51±0.76	10.34±0.66	10.39±1.14	9.77±0.94	10.66±1.32	11.82±0.90	11.76±1.71
	10_vs_11	7.46±0.71	8.57±2.10	8.49±1.64	8.87±0.83	8.95±1.01	9.40±0.95	9.59±0.86
	20_vs_20	6.24±1.13	6.42±1.71	9.06±0.71	10.54±0.47	10.19±0.66	11.81±0.46	9.29±0.58
	20_vs_23	5.47±1.14	6.48±1.61	6.47±0.75	8.23±0.39	7.42±0.66	8.21±0.72	8.22±0.37
zerg	5_vs_5	7.89±0.64	9.34±0.86	10.53±1.38	10.00±0.79	9.62±1.54	10.68±1.96	10.41±1.20
	10_vs_10	10.85±1.46	11.42±1.52	11.77±0.70	12.43±1.18	10.35±1.07	11.46±0.95	10.90±2.18
	10_vs_11	10.09±2.48	9.07±1.22	9.96±1.23	8.94±0.40	9.11±1.08	11.01±0.94	9.79±0.81
	20_vs_20	7.99±0.48	9.20±1.34	9.20±1.02	9.05±0.80	9.03±0.63	9.42±1.16	10.49±0.87
	20_vs_23	9.07±1.09	9.97±0.66	10.43±0.63	10.19±1.00	9.33±0.84	10.51±0.79	10.07±0.71
Hopper-v2	expert	147.31±67.94	107.85±65.54	545.67±820.56	2625.00±191.34	2018.73±972.03	2827.70±62.91	2690.72±58.63
	medium	149.62±96.75	107.54±66.86	244.66±267.46	794.41±69.19	295.53±227.14	822.55±66.21	807.53±122.18
	medium-replay	165.64±104.09	109.56±38.68	155.60±61.61	221.32±57.96	129.87±54.99	906.25±242.13	186.50±16.77
	medium-expert	119.12±77.13	95.57±69.53	58.75±26.06	1294.12±520.44	105.48±103.86	1362.44±522.87	1358.44±595.05
Ant-v2	expert	1016.36±196.48	1179.05±273.70	1927.73±174.10	1945.24±2.85	1884.13±27.83	2056.89±5.92	1949.99±3.28
	medium	907.33±32.23	1000.05±90.37	1424.33±3.09	1359.18±3.21	1346.22±49.81	1425.00±2.87	1354.59±2.48
	medium-replay	969.09±21.92	978.43±39.59	944.59±28.94	1111.12±57.78	987.50±33.87	1122.94±61.04	1072.06±41.44
	medium-expert	915.76±364.10	1132.93±282.16	738.47±250.19	1655.94±42.83	1182.46±405.08	1813.88±68.37	1559.59±86.77
HalfCheetah-v2	expert	1068.91±635.24	935.17±905.86	3636.95±80.87	3860.59±91.48	3829.99±88.77	4082.93±45.68	3843.72±149.37
	medium	575.92±724.82	445.19±403.87	2690.00±92.38	2532.35±81.86	2347.82±171.77	2664.71±54.19	2523.43±59.03
	medium-replay	412.30±310.54	233.49±270.11	861.58±173.54	2729.93±241.49	1258.49±1015.37	2855.02±242.25	2557.37±241.46
	medium-expert	-107.50±298.07	-275.92±544.54	1136.90±1608.33	3665.17±74.03	3601.04±155.60	3889.74±81.64	3605.58±70.37

In [278...]

pd.DataFrame.from_dict(ablation_mixer_results).map(analyze, tag="return").T

Out[278...]

		ComaDICE (ours)	ComaDICE (2-layer)
2c_vs_64zg	poor	12.15±0.51	11.45±0.88
	medium	16.30±0.66	11.21±0.85
	good	20.34±0.06	9.01±2.19
5m_vs_6m	poor	8.12±0.55	3.81±1.10
	medium	8.65±0.38	0.78±0.27
	good	8.66±0.50	7.69±0.14
6h_vs_8z	poor	11.37±0.58	10.30±0.34
	medium	12.83±0.22	9.06±0.62
	good	13.11±0.46	8.30±0.49
corridor	poor	6.36±0.47	1.47±0.75
	medium	12.90±0.62	3.90±1.70
	good	17.98±0.08	2.55±2.30
protoss	5_vs_5	14.41±1.15	10.54±1.45
	10_vs_10	14.55±1.81	11.23±1.61
	10_vs_11	13.18±0.86	9.48±0.45
	20_vs_20	14.83±0.99	9.54±0.90
	20_vs_23	13.26±0.90	7.09±2.16
terran	5_vs_5	10.70±1.53	8.30±0.80
	10_vs_10	11.82±0.90	8.84±1.08
	10_vs_11	9.40±0.95	6.36±1.16
	20_vs_20	11.81±0.46	7.80±0.93
	20_vs_23	8.21±0.72	6.61±0.89
zerg	5_vs_5	10.68±1.96	7.77±1.15
	10_vs_10	11.46±0.95	9.69±0.61
	10_vs_11	11.01±0.94	7.85±0.71
	20_vs_20	9.42±1.16	7.85±0.57
	20_vs_23	10.51±0.79	8.02±0.52
Hopper-v2	expert	2827.70±62.91	483.74±349.69
	medium	822.55±66.21	648.40±245.89
	medium-replay	906.25±242.13	441.87±260.77
	medium-expert	1362.44±522.87	402.28±288.17
Ant-v2	expert	2056.89±5.92	1582.97±160.42
	medium	1425.00±2.87	1198.87±53.92
	medium-replay	1122.94±61.04	1041.78±38.41
	medium-expert	1813.88±68.37	1426.63±171.41
HalfCheetah-v2	expert	4082.93±45.68	2159.39±658.01
	medium	2664.71±54.19	2026.66±244.30
	medium-replay	2855.02±242.25	1299.18±196.11
	medium-expert	3889.74±81.64	1336.27±381.88

In [278]: pd.DataFrame.from_dict(main_results).map(analyze, tag="winrate").T

Out[278...]

		BC	BCQ	CQL	ICQ	OMAR	OMIGA	ComaDICE (ours)
2c_vs_64zg	poor	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.62±1.25
	medium	1.88±1.53	2.50±3.64	2.50±3.64	1.88±1.53	1.25±1.53	6.25±5.59	8.75±6.96
	good	31.25±9.88	35.62±8.75	44.38±13.02	28.75±4.59	28.75±9.14	40.62±9.48	55.00±1.53
5m_vs_6m	poor	2.50±1.25	1.25±1.53	1.25±1.53	1.25±1.53	0.62±1.25	6.88±1.25	4.38±4.24
	medium	1.88±1.53	1.25±1.53	2.50±1.25	1.25±1.53	0.62±1.25	2.50±3.06	7.50±2.50
	good	2.50±2.34	1.88±2.50	1.88±1.53	3.75±2.34	3.75±1.25	6.88±1.25	8.12±3.19
6h_vs_8z	poor	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	1.88±3.75
	medium	1.88±1.53	1.88±1.53	1.88±1.53	2.50±1.25	1.88±1.53	1.25±1.53	3.12±1.98
	good	8.75±1.25	8.75±3.64	7.50±1.53	9.38±1.98	0.62±1.25	5.62±3.64	11.25±5.45
corridor	poor	0.00±0.00	0.00±0.00	0.00±0.00	0.62±1.25	0.00±0.00	0.00±0.00	0.62±1.25
	medium	15.00±2.34	23.12±1.53	14.37±1.53	22.50±3.06	11.88±2.34	23.75±5.08	27.34±3.41
	good	30.63±4.15	42.50±6.43	5.62±1.25	42.50±6.43	3.12±0.00	41.88±6.43	48.75±2.50
protoss	5_vs_5	36.88±8.71	16.25±2.34	10.00±4.15	36.88±9.14	21.25±4.15	33.12±5.45	46.25±6.06
	10_vs_10	36.25±10.57	9.38±5.59	26.25±7.55	28.12±6.56	13.75±7.02	40.00±10.72	50.62±8.71
	10_vs_11	19.38±4.59	10.00±4.15	10.62±5.45	12.50±4.42	12.50±3.42	16.25±6.06	20.00±4.24
	20_vs_20	37.50±4.42	6.25±1.98	11.88±4.15	32.50±8.05	23.75±2.50	36.25±5.08	47.50±7.76
	20_vs_23	13.75±1.53	1.25±1.53	0.00±0.00	12.50±5.59	11.25±7.81	12.50±8.15	13.75±5.80
terran	5_vs_5	30.00±4.24	12.50±6.25	9.38±7.91	23.12±5.80	14.37±4.68	28.12±4.42	30.63±8.24
	10_vs_10	29.38±5.80	6.88±6.06	9.38±5.59	16.88±5.80	15.00±4.59	29.38±3.19	32.50±5.80
	10_vs_11	16.25±3.64	3.75±4.59	7.50±6.43	5.00±4.24	9.38±5.59	12.50±5.23	19.38±5.38
	20_vs_20	26.25±10.38	5.00±3.19	10.62±4.24	15.62±3.42	7.50±7.29	21.88±4.42	29.38±3.75
	20_vs_23	4.38±4.24	0.00±0.00	0.00±0.00	7.50±6.12	5.00±4.24	4.38±2.50	9.38±5.23
zerg	5_vs_5	26.88±10.00	14.37±4.24	14.37±5.80	18.75±7.13	13.75±6.12	21.88±5.93	31.25±7.65
	10_vs_10	25.00±2.80	5.62±4.59	5.62±4.59	15.62±7.40	19.38±2.34	23.75±6.43	33.75±11.76
	10_vs_11	13.75±4.68	9.38±5.23	6.25±4.42	10.62±6.73	10.62±3.75	13.75±6.73	19.38±3.64
	20_vs_20	8.12±1.53	2.50±1.25	1.25±1.53	10.00±7.76	12.50±4.42	10.00±2.34	9.38±6.25
	20_vs_23	7.50±3.19	0.62±1.25	1.25±1.53	7.50±3.19	3.75±2.34	4.38±4.24	11.25±4.24
Hopper-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
Ant-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
HalfCheetah-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN

In [279...]

pd.DataFrame.from_dict(ablation_results).map(analyze, tag="winrate").T

Out[279...]

		alpha0.01	alpha0.1	alpha1		alpha10		alpha100
		soft_chisquare	soft_chisquare	soft_chisquare	chisquare	kl	soft_chisquare	soft_chisquare
2c_vs_64zg	poor	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.00±0.00	0.62±1.25	0.62±1.25
	medium	0.00±0.00	1.88±3.75	5.00±5.08	13.12±4.59	10.62±3.75	8.75±6.96	8.75±4.59
	good	0.62±1.25	0.00±0.00	40.62±3.95	55.62±3.06	54.37±1.53	55.00±1.53	51.88±1.53
5m_vs_6m	poor	0.00±0.00	0.00±0.00	4.38±4.68	3.75±3.06	3.75±3.64	4.38±4.24	1.88±1.53
	medium	0.00±0.00	0.00±0.00	8.12±6.43	6.25±2.80	5.00±3.75	7.50±2.50	7.50±3.75
	good	0.00±0.00	0.00±0.00	6.25±4.42	8.75±3.64	6.88±3.06	8.12±3.19	10.00±6.06
6h_vs_8z	poor	0.00±0.00	0.00±0.00	1.88±3.75	0.00±0.00	0.00±0.00	1.88±3.75	0.62±1.25
	medium	0.00±0.00	0.62±1.25	1.88±1.53	5.00±2.50	5.00±3.75	3.12±1.98	3.12±1.98
	good	0.00±0.00	0.00±0.00	7.50±5.80	9.38±4.42	9.38±1.98	11.25±5.45	7.50±7.29
corridor	poor	0.00±0.00	0.62±1.25	0.00±0.00	1.25±1.53	1.25±1.53	0.62±1.25	1.25±1.53
	medium	0.00±0.00	0.00±0.00	30.00±5.08	31.25±6.25	28.12±5.93	27.34±3.41	34.38±2.80
	good	0.00±0.00	4.38±8.75	48.75±4.68	49.38±5.38	48.12±1.53	48.75±2.50	49.38±3.64
protoss	5_vs_5	20.62±10.00	31.87±6.06	50.00±2.80	52.50±4.15	46.25±7.23	46.25±6.06	46.25±8.48
	10_vs_10	19.38±6.06	25.00±3.42	45.00±11.11	48.12±7.55	55.00±9.80	50.62±8.71	51.25±7.55
	10_vs_11	0.00±0.00	6.25±9.68	18.75±8.15	22.50±8.71	20.62±6.12	20.00±4.24	29.38±8.29
	20_vs_20	1.25±1.53	8.75±7.76	28.12±8.62	38.12±2.34	41.25±7.76	47.50±7.76	40.62±6.25
	20_vs_23	0.00±0.00	1.88±2.50	9.38±6.56	16.88±4.24	15.00±3.64	13.75±5.80	17.50±5.08
terran	5_vs_5	25.62±4.59	22.50±7.23	30.63±4.15	41.25±7.23	38.75±10.57	30.63±8.24	41.25±4.59
	10_vs_10	15.00±8.71	28.75±7.23	33.75±9.35	30.63±4.15	36.25±10.75	32.50±5.80	43.75±7.13
	10_vs_11	3.75±2.34	13.75±9.19	14.37±9.19	15.62±11.52	15.00±7.50	19.38±5.38	16.25±10.35
	20_vs_20	0.62±1.25	2.50±3.64	18.75±1.98	33.75±6.37	28.75±11.76	29.38±3.75	21.88±3.42
	20_vs_23	0.62±1.25	2.50±3.64	2.50±3.64	5.62±4.15	8.12±4.24	9.38±5.23	6.25±1.98
zerg	5_vs_5	10.00±4.59	20.00±5.80	28.75±4.59	29.38±8.97	33.12±13.35	31.25±7.65	25.00±8.62
	10_vs_10	13.75±8.97	20.62±8.29	29.38±8.97	31.25±7.65	26.25±5.08	33.75±11.76	31.87±6.67
	10_vs_11	9.38±9.48	12.50±6.85	16.88±3.19	11.25±1.53	16.25±7.23	19.38±3.64	17.50±9.19
	20_vs_20	0.00±0.00	1.88±1.53	6.88±6.06	7.50±3.19	11.25±7.02	9.38±6.25	12.50±3.95
	20_vs_23	1.25±1.53	3.75±2.34	12.50±3.95	10.62±3.19	10.00±2.34	11.25±4.24	11.88±6.06
Hopper-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
Ant-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
HalfCheetah-v2	expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-replay	NaN	NaN	NaN	NaN	NaN	NaN	NaN
	medium-expert	NaN	NaN	NaN	NaN	NaN	NaN	NaN

In [279...]

pd.DataFrame.from_dict(ablation_mixer_results).map(analyze, tag="winrate").T

Out[279...]

		ComaDICE (ours)	ComaDICE (2-layer)
2c_vs_64zg	poor	0.62±1.25	0.00±0.00
	medium	8.75±6.96	3.75±3.64
	good	55.00±1.53	19.38±5.00
5m_vs_6m	poor	4.38±4.24	3.12±0.00
	medium	7.50±2.50	1.25±1.53
	good	8.12±3.19	3.12±0.00
6h_vs_8z	poor	1.88±3.75	0.00±0.00
	medium	3.12±1.98	0.00±0.00
	good	11.25±5.45	1.88±2.50
corridor	poor	0.62±1.25	0.00±0.00
	medium	27.34±3.41	11.25±2.50
	good	48.75±2.50	23.12±8.05
protoss	5_vs_5	46.25±6.06	31.87±3.64
	10_vs_10	50.62±8.71	32.50±5.80
	10_vs_11	20.00±4.24	10.62±7.29
	20_vs_20	47.50±7.76	21.88±3.95
	20_vs_23	13.75±5.80	6.88±5.38
terran	5_vs_5	30.63±8.24	25.62±4.59
	10_vs_10	32.50±5.80	28.12±3.42
	10_vs_11	19.38±5.38	12.50±3.95
	20_vs_20	29.38±3.75	11.25±3.19
	20_vs_23	9.38±5.23	3.12±1.98
zerg	5_vs_5	31.25±7.65	20.62±4.68
	10_vs_10	33.75±11.76	21.25±7.23
	10_vs_11	19.38±3.64	13.12±4.15
	20_vs_20	9.38±6.25	5.62±1.25
	20_vs_23	11.25±4.24	3.12±3.42
Hopper-v2	expert	NaN	NaN
	medium	NaN	NaN
	medium-replay	NaN	NaN
	medium-expert	NaN	NaN
Ant-v2	expert	NaN	NaN
	medium	NaN	NaN
	medium-replay	NaN	NaN
	medium-expert	NaN	NaN
HalfCheetah-v2	expert	NaN	NaN
	medium	NaN	NaN
	medium-replay	NaN	NaN
	medium-expert	NaN	NaN

```
In [279...]: def select_results(results, select_alpha=True, tag="return"):
    new_results = {}
    for (env_name, mode), data in results.items():
        for algo, items in data.items():
            if isinstance(algo, tuple):
                if select_alpha:
                    algo = algo[0]
                else:
                    if algo[0] != "alpha10":
                        continue
                    algo = algo[1]
            if tag == "winrate" and env_name in MAMUJOCO_ENV_NAMES:
                continue
            if env_name not in new_results:
                new_results[env_name] = defaultdict(list)
            items = [item[max(item.keys())] for item in items]
            items = [item[tag] for item in items if tag in item]
            new_results[env_name][algo] += items
    return new_results
```

```
In [279...]: def create_box_figure(data, min_y, max_y, tag="return"):
    fig = go.Figure()
    for alpha, items in data.items():
        name = alpha.replace("alpha", "")
        fig.add_trace(go.Box(y=items, name=name, marker_color=colors[0], boxpoints=False))
    fig.update_layout(template='simple_white', margin=dict(l=0, r=0, t=0, b=0, pad=0, autoexpand=True))
    fig.update_layout(height=120, width=160)
    if tag == "return":
        fig.update_yaxes(range=[min_y, max_y], tickformat="~s")
    else:
        fig.update_yaxes(range=[min_y, max_y], tickformat=".0%")
    fig.update_layout(showlegend=False)
    return fig
```

```
In [279...]: def show_box(alpha_box_figures, env_names, tag="returns", y_range=None):
    fig = make_subplots(rows=1, cols=len(env_names), subplot_titles=env_names)
    for i, env_name in enumerate(env_names):
```

```

plotly_fig = alpha_box_figures[env_name]
plotly_fig.write_image(f"graphs/{env_name}_box_{tag}.pdf")
fig.add_traces(plotly_fig.data, rows=1, cols=1)
fig.update_layout(template='simple_white', margin=dict(l=40, r=40, t=40, b=40, pad=0, autoexpand=True))
fig.update_layout(height=180, width=200*len(env_names))

if tag == "winrates":
    tickformat = ".0%"
else:
    tickformat = "~S"
fig.update_yaxes(range=y_range, tickformat=tickformat)
fig.update_layout(showlegend=False)
fig.show("svg")

```

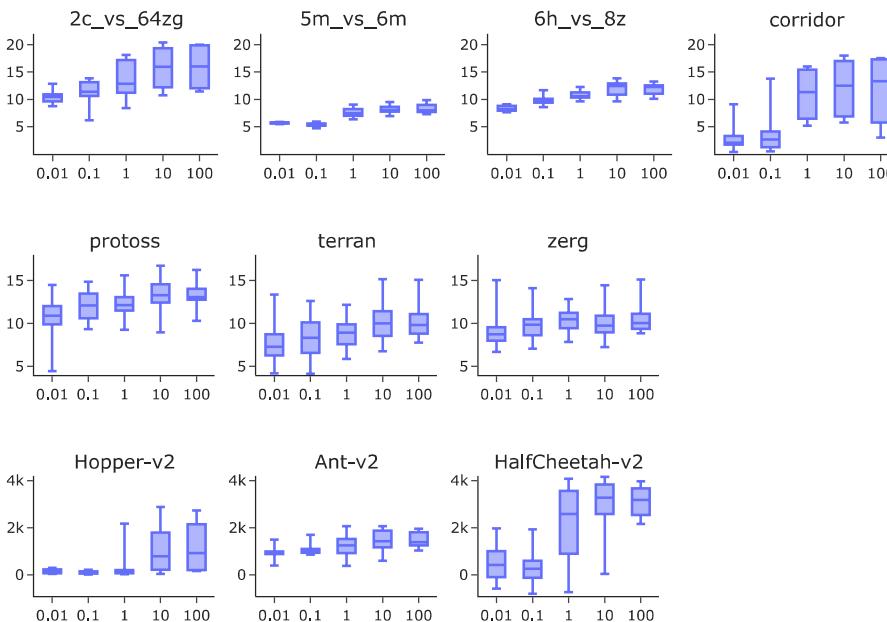
In [279...]:

```

alpha_results = select_results(ablation_results, tag="return")
alpha_box_figures = {}
y_range_dict = {
    "smacv1": (0.01, 22),
    "smacv2": (4, 18),
    "mamujoco": (-900, 4200),
}
for env_name, data in alpha_results.items():
    if env_name in SMACV1_ENV_NAMES:
        min_y, max_y = y_range_dict["smacv1"]
    elif env_name in SMACV2_ENV_NAMES:
        min_y, max_y = y_range_dict["smacv2"]
    else:
        min_y, max_y = y_range_dict["mamujoco"]
    alpha_box_figures[env_name] = create_box_figure(data, min_y, max_y, tag="return")

show_box(alpha_box_figures, SMACV1_ENV_NAMES, tag="returns", y_range=y_range_dict["smacv1"])
show_box(alpha_box_figures, SMACV2_ENV_NAMES, tag="returns", y_range=y_range_dict["smacv2"])
show_box(alpha_box_figures, MAMUJOCO_ENV_NAMES, tag="returns", y_range=y_range_dict["mamujoco"])

```



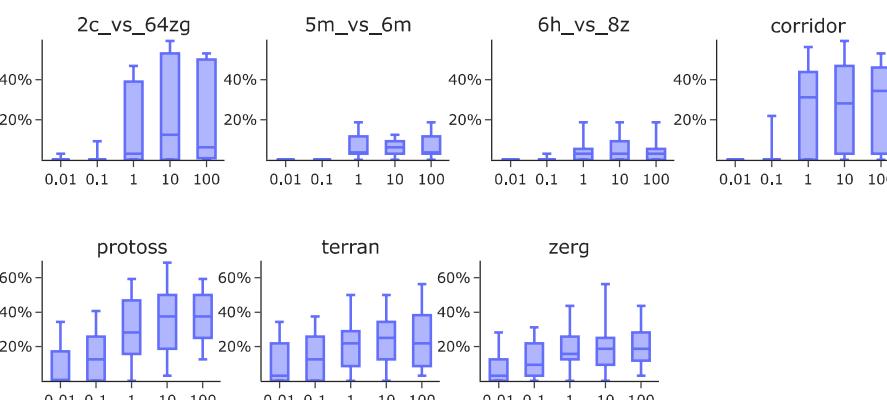
In [279...]:

```

alpha_results = select_results(ablation_results, tag="winrate")
alpha_box_figures = {}
for env_name, data in alpha_results.items():
    min_y, max_y = (1e-4, 0.599) if env_name in SMACV1_ENV_NAMES else (1e-4, 0.699)
    alpha_box_figures[env_name] = create_box_figure(data, min_y, max_y, tag="winrate")

show_box(alpha_box_figures, SMACV1_ENV_NAMES, tag="winrates", y_range=(1e-4, 0.599))
show_box(alpha_box_figures, SMACV2_ENV_NAMES, tag="winrates", y_range=(1e-4, 0.699))

```



In [279...]:

```

def smooth(scalars, weight):
    last = 0
    smoothed = []
    for num_acc, next_val in enumerate(scalars):
        last = last * weight + (1 - weight) * next_val
        smoothed.append(last / (1 - math.pow(weight, num_acc+1)))
    return smoothed

```

In [279...]:

```

def create_scatters(data, y_range=None, tag="return", smooth_weight=0.5):
    fig = go.Figure()
    all_values = []
    for algo, items in data.items():

```

```

all_items = defaultdict(list)
for item in items:
    for key, value in item.items():
        if tag in value:
            all_items[key].append(value[tag])

if len(all_items) == 0:
    continue
if '2-layer' in algo:
    continue

steps = sorted(all_items.keys())
values = [np.mean(all_items[key]) for key in steps]
stds = [np.std(all_items[key]) for key in steps]

values = smooth(values, smooth_weight)

uppers = [value + std for value, std in zip(values, stds)]
lowers = [value - std for value, std in zip(values, stds)]

if tag == "winrate":
    uppers = [min(1.0, value) for value in uppers]
    lowers = [max(0.0, value) for value in lowers]
all_values += values

color = COLOR_MAPS.get(algo, colors[2])
fig.add_trace(go.Scatter(x=steps, y=values, mode="lines", name=algo, line_color=color, line_width=1.5))
fig.add_trace(go.Scatter(x=steps+steps[::-1], y=uppers+lowers[::-1], fill="toself", fillcolor=color, line_color=color, opacity=0.05, line_width=1))

fig.update_layout(template='simple_white', margin=dict(l=0, r=0, t=0, b=0, pad=0, autoexpand=True))
fig.update_layout(height=100, width=180)
fig.update_xaxes(range=[0, 100], dtick=50, minor=dict(ticklen=3, nticks=4))
if tag == "winrate":
    tickformat = ".0%"
else:
    tickformat = "~s"
fig.update_yaxes(range=y_range, tickformat=tickformat)
fig.update_layout(showlegend=False)
return fig

```

```

In [279... plotly_figs = {}
y_range_dict = {
    "2c_vs_64zb": (9, 21),
    "5m_vs_6m": (3, 9.5),
    "6h_vs_8z": (8.1, 13.5),
    "corridor": (1, 19.5),
    "protoss": (4, 16.5),
    "terran": (1, 14.5),
    "zerg": (2, 14),
    "Hopper-v2": (-500, 3200),
    "Ant-v2": (-900, 2400),
    "HalfCheetah-v2": (-900, 4500),
}
for (env_name, mode), data in main_results.items():
    y_range = y_range_dict.get(env_name)
    plotly_figs[(env_name, mode)] = create_scatters(data, y_range=y_range, tag="return")

```

```

In [280... def update_legend(fig, tag="returns"):
    trace_names = []
    for trace in fig.data:
        if trace.name is not None and trace.name not in trace_names:
            trace_names.append(trace.name)
            trace.update(showlegend=True)
        else:
            trace.update(showlegend=False)
    fig.update_layout(legend=dict(orientation="h", yanchor="bottom", y=1.05, xanchor="right", x=1))
if tag == "winrates":
    fig.update_yaxes(range=[0, None], tickformat=".0%")
else:
    fig.update_yaxes(tickformat=~s)

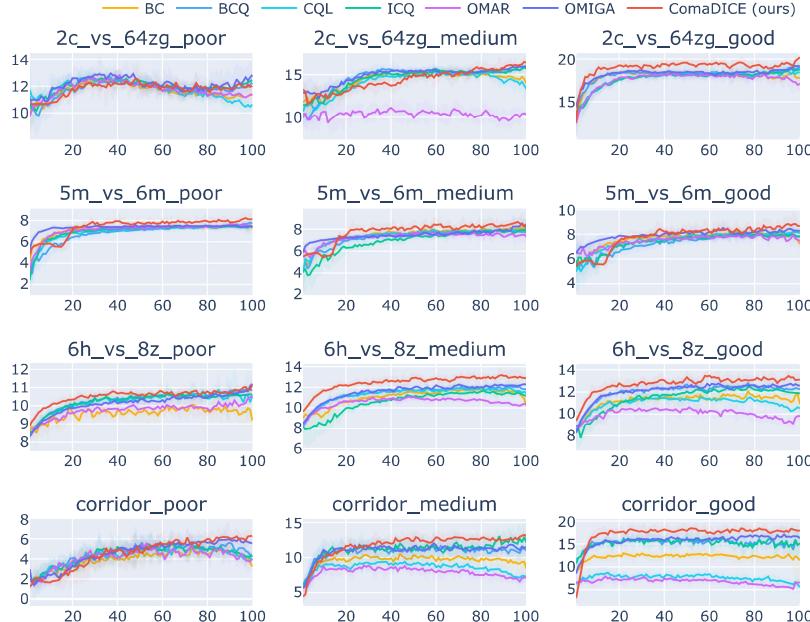
```

```

In [280... fig = make_subplots(rows=4, cols=3, subplot_titles=[f"{env_name}_{mode}" for env_name in SMACV1_ENV_NAMES for mode in SMACV1_MODES])
for i, mode in enumerate(SMACV1_MODES):
    for j, env_name in enumerate(SMACV1_ENV_NAMES):
        plotly_fig = plotly_figs[(env_name, mode)]
        plotly_fig.write_image(f"graphs/{env_name}_{mode}_returns.pdf")
        fig.add_traces(plotly_fig.data, rows=j+1, cols=i+1)
fig.update_layout(height=640, width=800, title_text="SMACv1")
update_legend(fig, tag="returns")
fig.show("svg")

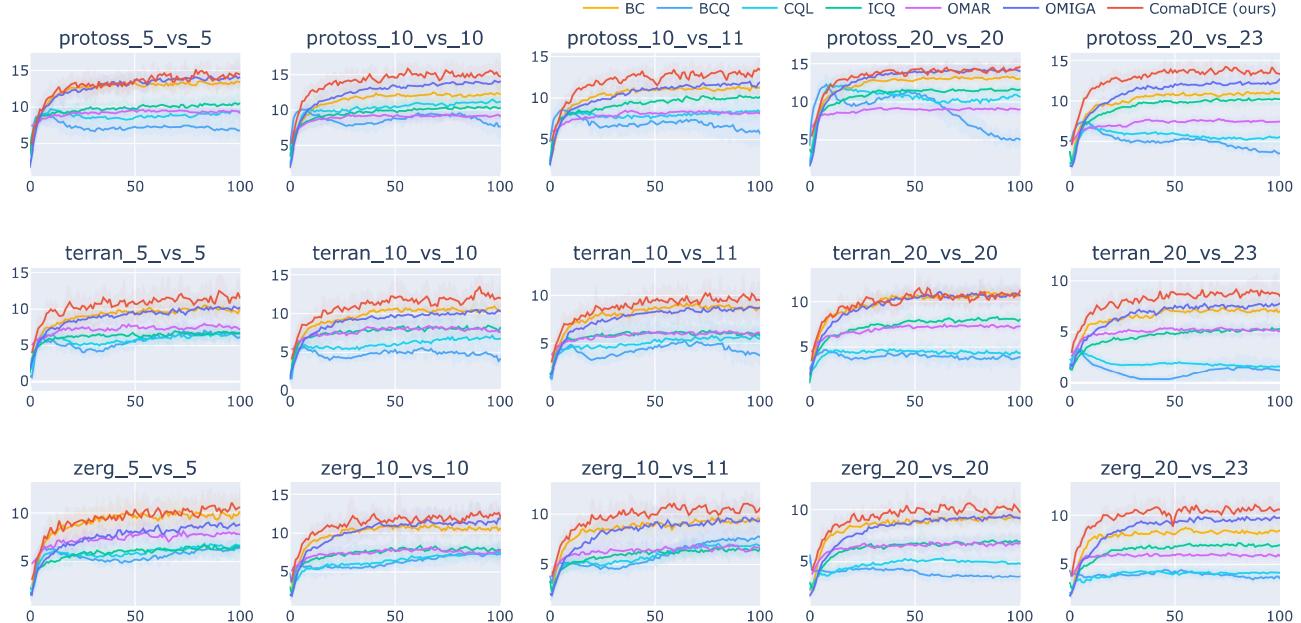
```

SMACv1



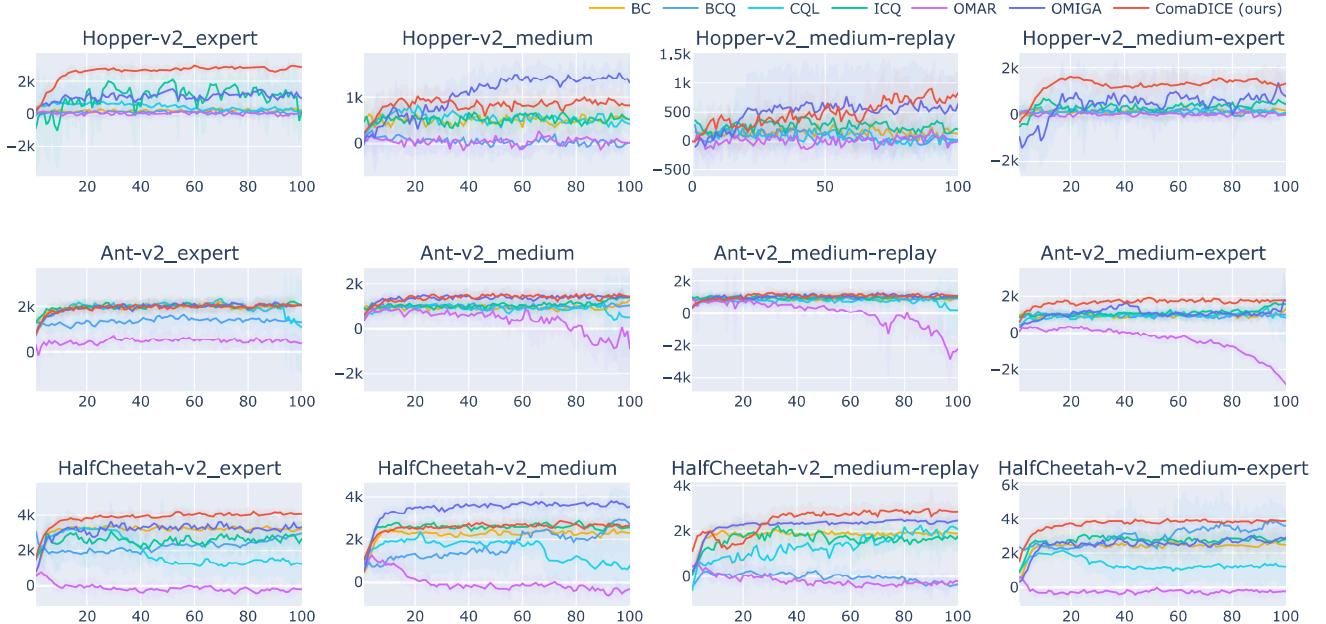
```
In [280]: fig = make_subplots(rows=3, cols=5, subplot_titles=[f"{env_name}_{mode}" for env_name in SMACV2_ENV_NAMES for mode in SMACV2_MODES])
for i, mode in enumerate(SMACV2_MODES):
    for j, env_name in enumerate(SMACV2_ENV_NAMES):
        plotly_fig = plotly_figs[(env_name, mode)]
        plotly_fig.write_image(f"graphs/{env_name}_{mode}_returns.pdf")
        fig.add_traces(plotly_fig.data, rows=j+1, cols=i+1)
fig.update_layout(height=640, width=1200, title_text="SMACV2")
update_legend(fig, tag="returns")
fig.show("svg")
```

SMACv2



```
In [280]: fig = make_subplots(rows=3, cols=4, subplot_titles=[f"{env_name}_{mode}" for env_name in MAMUJOCO_ENV_NAMES for mode in MAMUJOCO_MODES])
for i, mode in enumerate(MAMUJOCO_MODES):
    for j, env_name in enumerate(MAMUJOCO_ENV_NAMES):
        plotly_fig = plotly_figs[(env_name, mode)]
        plotly_fig.write_image(f"graphs/{env_name}_{mode}_returns.pdf")
        fig.add_traces(plotly_fig.data, rows=j+1, cols=i+1)
fig.update_layout(height=640, width=1200, title_text="MaMuJoco")
update_legend(fig, tag="returns")
fig.show("svg")
```

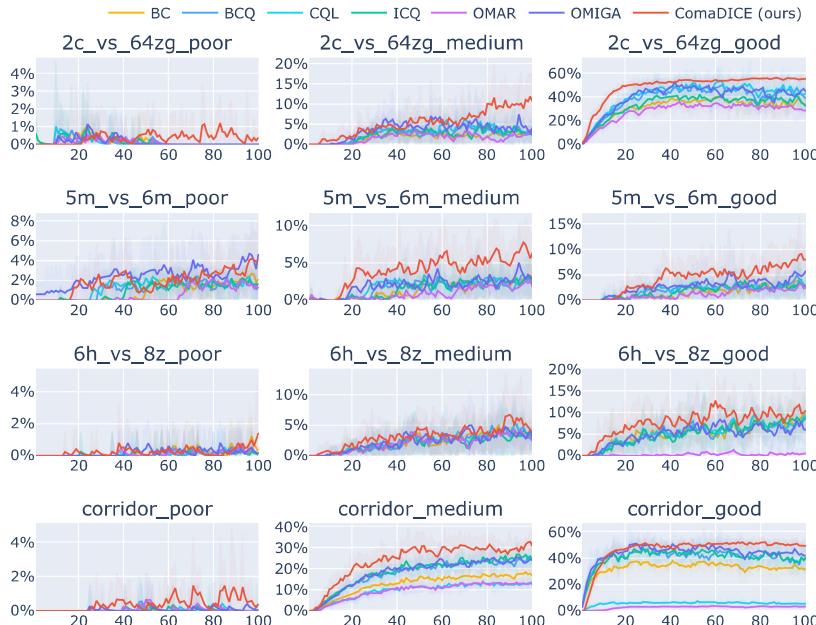
MaMujoco



```
In [280]: plotly_figs = {}
y_range_dict = {
    "2c_vs_64zg": (1e-4, 0.599),
    "5m_vs_6m": (1e-4, 0.12),
    "6h_vs_8z": (1e-4, 0.16),
    "corridor": (1e-4, 0.599),
    "protoss": (1e-4, 0.599),
    "terran": (1e-4, 0.599),
    "zerg": (1e-4, 0.599),
}
for (env_name, mode), data in main_results.items():
    if env_name in MAMUJOCO_ENV_NAMES:
        continue
    y_range = y_range_dict.get(env_name)
    plotly_figs[(env_name, mode)] = create_scatters(data, y_range, "winrate", 0.6)
```

```
In [280]: fig = make_subplots(rows=4, cols=3, subplot_titles=[f"{env_name}_{mode}" for env_name in SMACV1_ENV_NAMES for mode in SMACV1_MODES])
for i, mode in enumerate(SMACV1_MODES):
    for j, env_name in enumerate(SMACV1_ENV_NAMES):
        plotly_fig = plotly_figs[(env_name, mode)]
        plotly_fig.write_image(f"graphs/{env_name}_{mode}_winrates.pdf")
        fig.add_traces(plotly_fig.data, rows=j+1, cols=i+1)
fig.update_layout(height=640, width=800, title_text="SMACv1")
update_legend(fig, tag="winrates")
fig.show("svg")
```

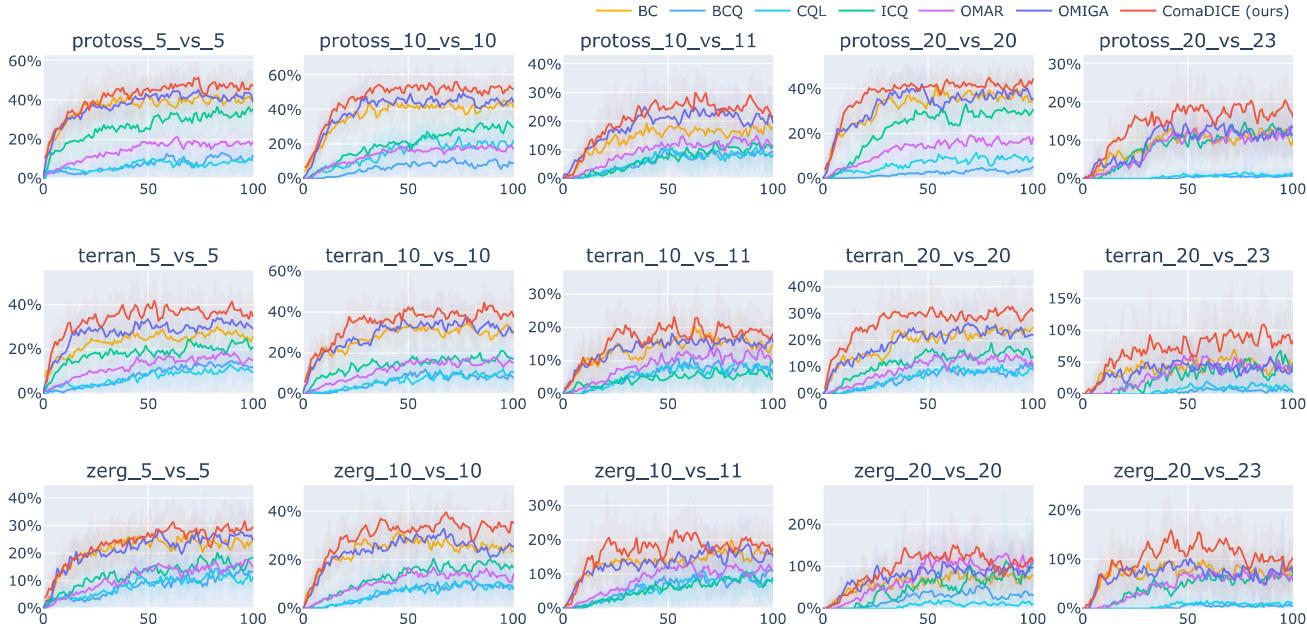
SMACv1



```
In [280]: fig = make_subplots(rows=3, cols=5, subplot_titles=[f"{env_name}_{mode}" for env_name in SMACV2_ENV_NAMES for mode in SMACV2_MODES])
for i, mode in enumerate(SMACV2_MODES):
    for j, env_name in enumerate(SMACV2_ENV_NAMES):
        plotly_fig = plotly_figs[(env_name, mode)]
        plotly_fig.write_image(f"graphs/{env_name}_{mode}_winrates.pdf")
        fig.add_traces(plotly_fig.data, rows=j+1, cols=i+1)
```

```
fig.update_layout(height=640, width=1200, title_text="SMACv2")
update_legend(fig, tag="winrates")
fig.show("svg")
```

SMACv2



```
In [280...]
fig.update_layout(template='simple_white', margin=dict(l=4, r=4, t=4, b=4, pad=4, autoexpand=True))
fig.update_layout(height=300, width=1000, title_text=None)
fig.update_layout(legend=dict(orientation="h", yanchor="bottom", y=1.5, xanchor="right", x=1))
fig.write_image(f"graphs/legends.pdf")
```

```
In [280...]
def get_data_info(filename):
    data = np.load(f"offline_data/{filename}.npz", allow_pickle=True)
    states = data["states"]
    obs = data["obs"]
    actions = data["actions"]
    rewards = data["rewards"]
    dones = data["dones"]
    avails = data.get("avails")
    actives = data["actives"]

    is_last = np.zeros_like(dones)
    is_last[:, :-1] = dones[:, 1:]

    n_trajs, _, n_agents, ob_dim = obs.shape
    st_dim = states.shape[-1]
    ac_dim = avails.shape[-1] if avails is not None else actions.shape[-1]
    if avails is None:
        st_dim = st_dim * n_agents
    rewards = rewards.sum(1)
    avg_reward = np.mean(rewards)
    std_reward = np.std(rewards)
    n_trans = np.sum(actives)
    n_trajs = f"{n_trajs/1e3:.1f}K" if n_trajs < 1e6 else f"{n_trajs/1e3:.0f}K"
    n_trans = f"{n_trans/1e3:.1f}K" if n_trans < 1e6 else f"{n_trans/1e3:.0f}K"
    return {
        "n_trajs": n_trajs,
        "n_trans": n_trans,
        "n_agents": n_agents,
        "st_dim": st_dim,
        "ob_dim": ob_dim,
        "ac_dim": ac_dim,
        "reward": f'{avg_reward:.1f}±{std_reward:.1f}',
    }
```

```
In [280...]
data_info = {}
with Pool(4) as p:
    tasks = []
    for env_name in SMACV1_ENV_NAMES:
        for mode in SMACV1_MODES:
            tasks.append((env_name, mode, p.submit(get_data_info, f"{env_name}_{mode}")))
    for env_name in SMACV2_ENV_NAMES:
        for mode in SMACV2_MODES:
            tasks.append((env_name, mode, p.submit(get_data_info, f"{env_name}_{mode}_medium")))
    for env_name in MAMUJOCO_ENV_NAMES:
        for mode in MAMUJOCO_MODES:
            env_conf_dict = {
                "Hopper-v2": "3x1",
                "Ant-v2": "2x4",
                "HalfCheetah-v2": "6x1",
            }
            env_conf = env_conf_dict[env_name]
            tasks.append((env_name, mode, p.submit(get_data_info, f"{env_name}-{env_conf}-{mode}")))
    for env_name, mode, task in tqdm(tasks):
        data_info[(env_name, mode)] = task.result()
```

100% |██████████| 39/39 [00:25<00:00, 1.54it/s]

```
In [281...]
df = pd.DataFrame(data_info).T
df
```

		n_trajs	n_trans	n_agents	st_dim	ob_dim	ac_dim	reward
2c_vs_64zg	poor	0.3K	21.7K	2	675	478	70	8.9±1.0
	medium	1.0K	75.9K	2	675	478	70	13.0±1.4
	good	1.0K	118.4K	2	675	478	70	19.9±1.3
5m_vs_6m	poor	1.0K	113.7K	5	156	124	12	8.5±1.2
	medium	1.0K	138.6K	5	156	124	12	11.0±0.6
	good	1.0K	138.7K	5	156	124	12	20.0±0.0
6h_vs_8z	poor	1.0K	145.5K	6	213	172	14	9.1±0.8
	medium	1.0K	177.1K	6	213	172	14	12.0±1.3
	good	1.0K	228.2K	6	213	172	14	17.8±2.1
corridor	poor	1.0K	307.6K	6	435	346	30	4.9±1.7
	medium	1.0K	756.1K	6	435	346	30	13.1±1.3
	good	1.0K	601.0K	6	435	346	30	19.9±1.0
protoss	5_vs_5	1.0K	60.8K	5	130	92	11	16.8±6.3
	10_vs_10	1.0K	68.3K	10	310	182	16	15.7±5.2
	10_vs_11	1.0K	62.9K	10	327	191	17	15.3±5.7
	20_vs_20	1.0K	76.7K	20	820	362	26	16.2±4.7
	20_vs_23	1.0K	65.0K	20	901	389	29	14.0±4.5
terran	5_vs_5	1.0K	47.6K	5	120	82	11	15.2±7.2
	10_vs_10	1.0K	56.4K	10	290	162	16	14.7±6.2
	10_vs_11	1.0K	52.5K	10	306	170	17	12.1±5.7
	20_vs_20	1.0K	63.0K	20	780	322	26	14.0±6.0
	20_vs_23	1.0K	51.3K	20	858	346	29	11.7±5.7
zerg	5_vs_5	1.0K	27.5K	5	120	82	11	10.4±5.0
	10_vs_10	1.0K	31.9K	10	290	162	16	14.7±6.0
	10_vs_11	1.0K	30.9K	10	306	170	17	12.0±5.1
	20_vs_20	1.0K	35.4K	20	780	322	26	12.3±4.2
	20_vs_23	1.0K	32.8K	20	858	346	29	10.8±4.0
Hopper-v2	expert	1.5K	998.9K	3	42	14	1	2452.0±1097.9
	medium	4.0K	915.4K	3	42	14	1	723.6±211.7
	medium-replay	4.2K	1311K	3	42	14	1	746.4±671.9
	medium-expert	5.5K	1914K	3	42	14	1	1190.6±973.4
Ant-v2	expert	1.0K	1000K	2	226	113	4	2055.1±22.1
	medium	1.0K	1000K	2	226	113	4	1418.7±37.0
	medium-replay	1.8K	1750K	2	226	113	4	1029.5±141.3
	medium-expert	2.0K	2000K	2	226	113	4	1736.9±319.6
HalfCheetah-v2	expert	1.0K	1000K	6	138	23	1	2785.1±1053.1
	medium	1.0K	1000K	6	138	23	1	1425.7±520.1
	medium-replay	1.0K	1000K	6	138	23	1	655.8±590.4
	medium-expert	2.0K	2000K	6	138	23	1	2105.4±1073.2