AA203
Optimal and Learning-based Control

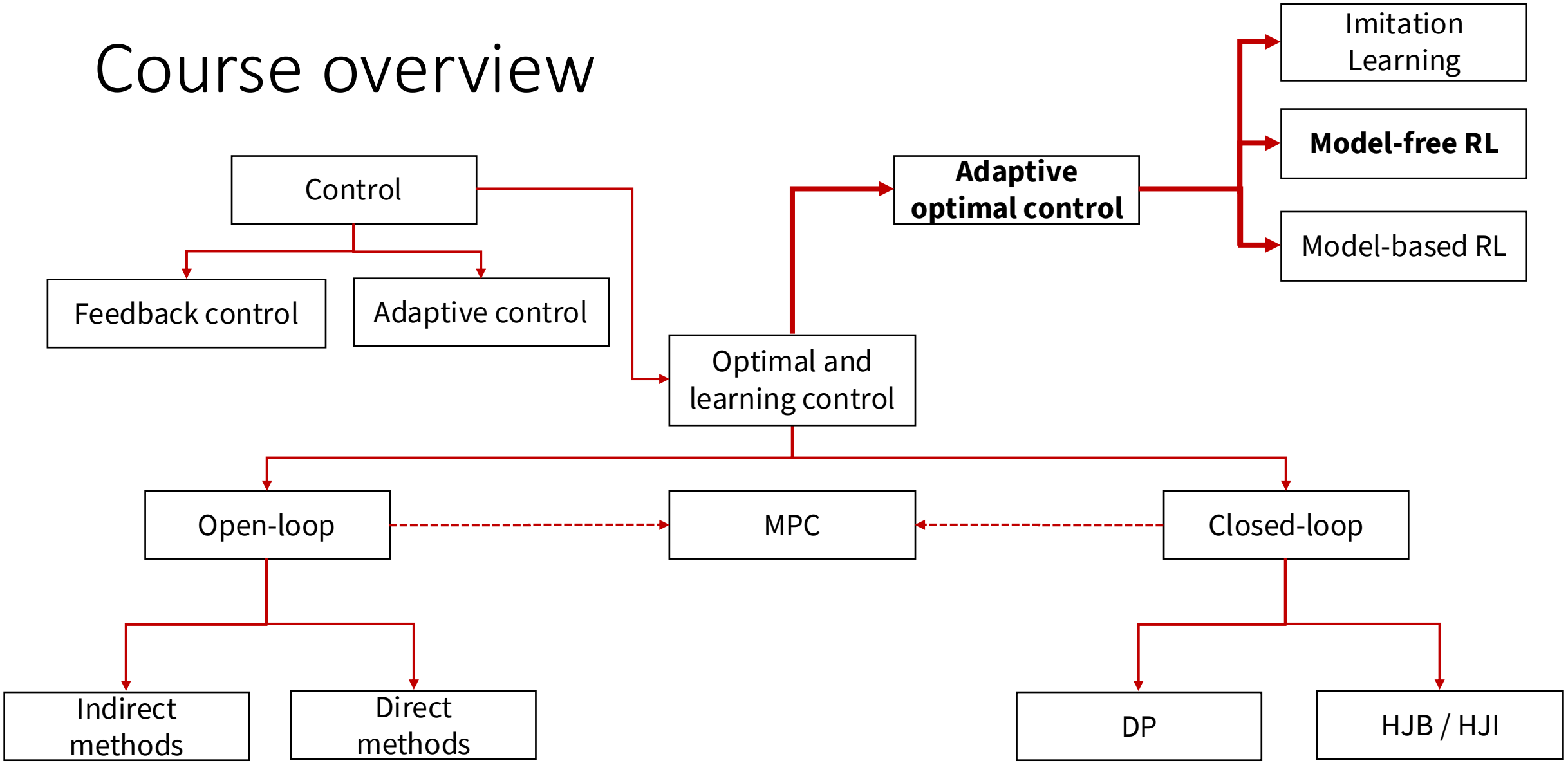
Fundamentals of Reinforcement Learning

Stanford University

ASL

Autonomous Systems Lab

Course overview



Outline

Recap: The RL problem and exact methods (based on dynamic programming)

From exact methods to model-free control

- Monte Carlo Learning
- Temporal-Difference (TD) Learning

The skeleton of an RL algorithm

Recap: Markov Decision Process

State: $x \in \mathcal{X}$

Action: $u \in \mathcal{U}$

Transition function / Dynamics: $T(x_t \mid x_{t-1}, u_{t-1}) = p(x_t \mid x_{t-1}, u_{t-1})$

Reward function: $r_t = R(x_t, u_t): \mathcal{X} \times \mathcal{U} \to \mathbb{R}$

Discount factor: $\gamma \in (0,1)$

Typically represented as a tuple

$$\mathcal{M} = (\mathcal{X}, \mathcal{U}, T, R, \gamma)$$

Goal: choose a policy that maximizes cumulative (discounted) reward

$$\pi^* = \underset{\pi}{\text{argmax}}\ \mathbb{E}_p\left[\sum_{t \geq 0} \gamma^t R\big(x_t, \pi(x_t)\big)\right]$$

Recap: Value Functions and Bellman Equations

The optimal value function satisfies Bellman's equation:

$$V^*\left(x_t\right) = \max_u \left(R\left(x_t, u_t\right) + \gamma \sum_{x_{t+1} \in X} T\left(x_{t+1} \mid x_t, u_t\right) V^*\left(x_{t+1}\right) \right)$$

Bellman Optimality Equation

For any stationary policy π, the values $\mathrm{V}_\pi(x) := \mathbb{E}\left[\sum_{t \geq 0} \gamma^t R\left(x_t, \pi\left(x_t\right)\right) \right]$ are the unique solution to the equation

$$\begin{aligned} \mathrm{V}_\pi\left(x_t\right) &= \mathbb{E}_\pi\left[R\left(x_t, \pi\left(x_t\right)\right) + \gamma \mathrm{V}_\pi\left(x_{t+1}\right)\right] \\ &= R\left(x_t, \pi\left(x_t\right)\right) + \gamma \sum_{x_{t+1} \in X} T\left(x_{t+1} \mid x_t, \pi\left(x_t\right)\right) \mathrm{V}_\pi\left(x_{t+1}\right) \end{aligned}$$

Bellman Expectation Equation

Recap: Value Functions and Bellman Equations

The optimal state-action value function (Q function) $Q^*(x, u)$ satisfies Bellman's equation:

$$Q^*(x_t, u_t) = R(x_t, u_t) + \gamma \sum_{x_{t+1} \in X} T(x_{t+1} \mid x_t, u_t) \max_{u_{t+1}} Q^*(x_{t+1}, u_{t+1})$$

Bellman Optimality Equation

For any stationary policy π, the corresponding Q function satisfies

$$Q_\pi(x_t, u_t) = R(x_t, u_t) + \gamma \sum_{x_{t+1} \in X} T(x_{t+1} \mid x_t, u_t) Q_\pi\big(x_{t+1}, \pi(x_{t+1})\big)$$

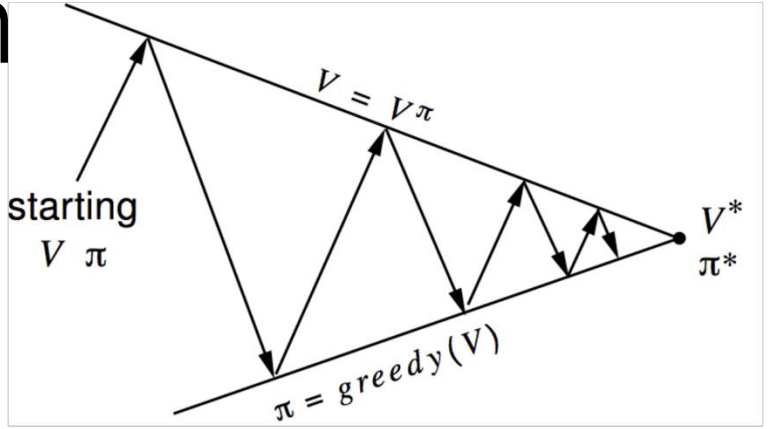
Bellman Expectation Equation

Solving MDPs

In previous lectures, we resorted to exact methods

Problem	Bellman Equation	Algorithm
Prediction	Bellman Expectation Equation	Iterative Policy Evaluation
Control	Bellman Expectation Equation + Greedy Policy Improvement	Policy Iteration
Control	Bellman Optimality Equation	Value Iteration

(Another look at) Policy Iteration



Given policy π. For $k = 1,\ldots$

Evaluate the policy π_k

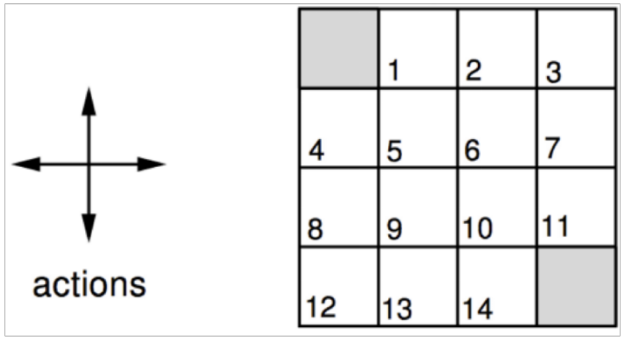
$$\mathrm{V}_{k+1}\left(x_t\right) = R\left(x_t, \pi_k\left(x_t\right)\right) + \gamma \sum_{x_{t+1} \in X} T\left(x_{t+1} \mid x_t, \pi_k\left(x_t\right)\right) \mathrm{V}_k\left(x_{t+1}\right)$$

Improve the policy π by acting greedily w.r.t. V_π

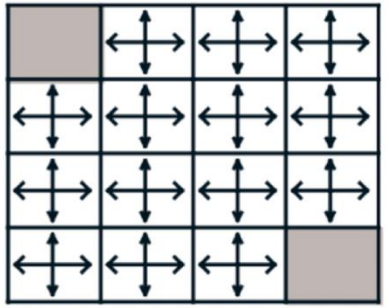
$$\pi_{k+1}(x) = \arg\max_u \left(R(x,u) + \gamma \sum_{x_{t+1} \in \mathcal{X}} T\left(x_{t+1} \mid x_t, u_t\right) V_{k+1}\left(x_{t+1}\right) \right)$$

Example: Grid World

From Sutton and Barto, Reinforcement Learning: An Introduction (Chapter 4)



- Nonterminal states 1, …, 14. Terminal states as shaded squared
- Reward is -1 until the terminal state is reached
- Controls leading out of the grid leave state unchanged
- Undiscounted MDP ($\gamma = 1$)
- We want to evaluate a uniform random policy

	$V_k(x)$ for the random policy	Greedy policy w.r.t. $V_k(x)$
$k=0$	0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0	 random policy
$k=1$	0.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 0.0	
$k=2$	0.0 -1.7 -2.0 -2.0 -1.7 -2.0 -2.0 -2.0 -2.0 -2.0 -2.0 -1.7 -2.0 -2.0 -1.7 0.0	

$V_k(x)$ for the random policy Greedy policy w.r.t. $V_k(x)$

$k = 3$

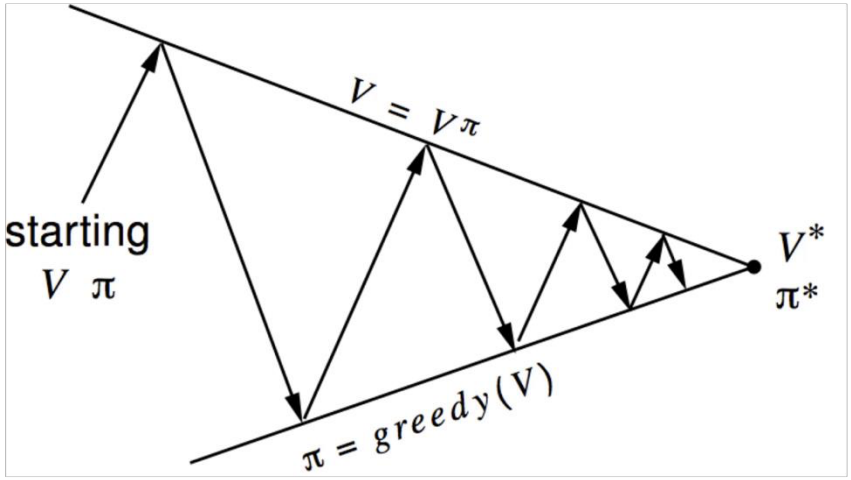
0.0	-2.4	-2.9	-3.0
-2.4	-2.9	-3.0	-2.9
-2.9	-3.0	-2.9	-2.4
-3.0	-2.9	-2.4	0.0

$k = 10$

0.0	-6.1	-8.4	-9.0
-6.1	-7.7	-8.4	-8.4
-8.4	-8.4	-7.7	-6.1
-9.0	-8.4	-6.1	0.0

$k = \infty$

0.0	-14.	-20.	-22.
-14.	-18.	-20.	-20.
-20.	-20.	-18.	-14.
-22.	-20.	-14.	0.0



$$\pi_{k+1}(x) = \arg\max_u \left(R(x,u) + \gamma \sum_{x_{t+1} \in \mathcal{X}} T\left(x_{t+1} \mid x_t, u_t\right) V_{k+1}\left(x_{t+1}\right) \right)$$

$V_k(x)$ for the random policy Greedy policy w.r.t. $V_k(x)$

$k = 3$

0.0	-2.4	-2.9	-3.0
-2.4	-2.9	-3.0	-2.9
-2.9	-3.0	-2.9	-2.4
-3.0	-2.9	-2.4	0.0

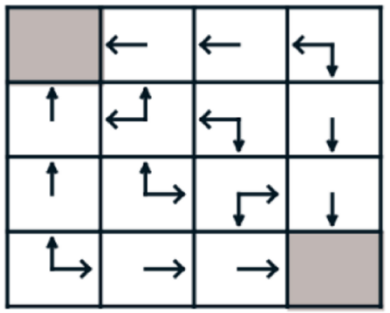
$k = 10$

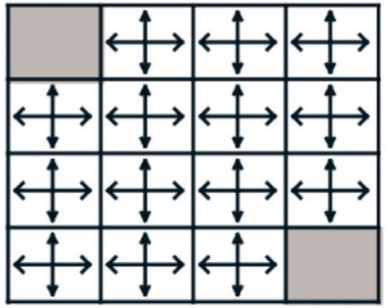
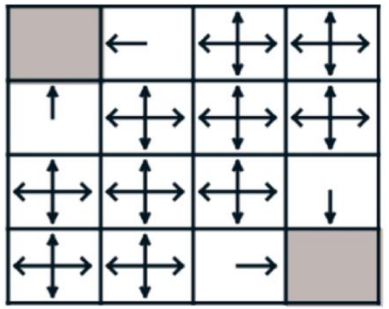
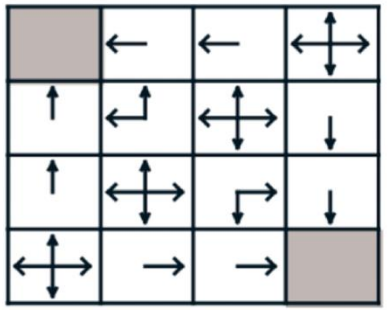
0.0	-6.1	-8.4	-9.0
-6.1	-7.7	-8.4	-8.4
-8.4	-8.4	-7.7	-6.1
-9.0	-8.4	-6.1	0.0

$k = \infty$

0.0	-14.	-20.	-22.
-14.	-18.	-20.	-20.
-20.	-20.	-18.	-14.
-22.	-20.	-14.	0.0

optimal policy



	$V_k(x)$ for the random policy	Greedy policy w.r.t. $V_k(x)$
$k=0$	0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0	 ← random policy
$k=1$	0.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 -1.0 0.0	
$k=2$	0.0 -1.7 -2.0 -2.0 -1.7 -2.0 -2.0 -2.0 -2.0 -2.0 -2.0 -1.7 -2.0 -2.0 -1.7 0.0	

Solving MDPs

In previous lectures, we resorted to exact methods

Problem	Bellman Equation	Algorithm
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Control	Bellman Optimality Equation	Value Iteration

All of these formulations require a model of the MDP!

To solve unknown MDPs, we'll use interactions with the environment

Limitations of exact methods (such as Policy/Value Iteration):

- Update equations (i.e., Bellman equations) require access to dynamics model $T(x_{t+1} \mid x_t, u_t)$ — Sampling-based approximations
- Iteration over (and storage of) all states and actions requires small, discrete state-action space — Function approximation

Outline

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- Temporal-Difference (TD) Learning

The skeleton of an RL algorithm

Monte Carlo Reinforcement Learning

- MC methods learn directly from episodes of experience
- MC is model-free: no knowledge of MDP transitions / rewards
- MC uses the simplest possible idea: value = mean return
  - Recall that the return is the total discounted reward:

$$G_t = R_{t+1} + \gamma R_{t+2} + \cdots + \gamma^{T-1} R_T$$

- Caveat: can only apply MC to episodic MDPs
  - All episodes must terminate

Monte Carlo Policy Evaluation

- Let's consider Monte Carlo methods for learning the state-value function $V_\pi(x)$ from episodes of experience under policy π
- Recall that the value function is the expected return

$$G_t = R_{t+1} + \gamma R_{t+2} + \cdots + \gamma^{T-1} R_T$$

$$V_\pi(x_t) = \mathbb{E}\left[\sum_{t' \geq t} \gamma^{t'} R\left(x_{t'}, \pi(x_{t'})\right)\right] = \mathbb{E}[G_t \mid x_t]$$

- Monte-Carlo policy evaluation uses empirical mean return instead of expected return

Monte Carlo Policy Evaluation

First-visit

- To evaluate state x
- The first time-step t that state x is visited in an episode
- Increment counter $N(x) \leftarrow N(x) + 1$
- Increment total return $S(x) \leftarrow S(x) + G_t$
- Value is estimated by mean return $\hat{V}(x) = S(x)/N(x)$
- By law of large numbers $\hat{V}(x) \rightarrow V_\pi(x)$ as $N(x) \rightarrow \infty$

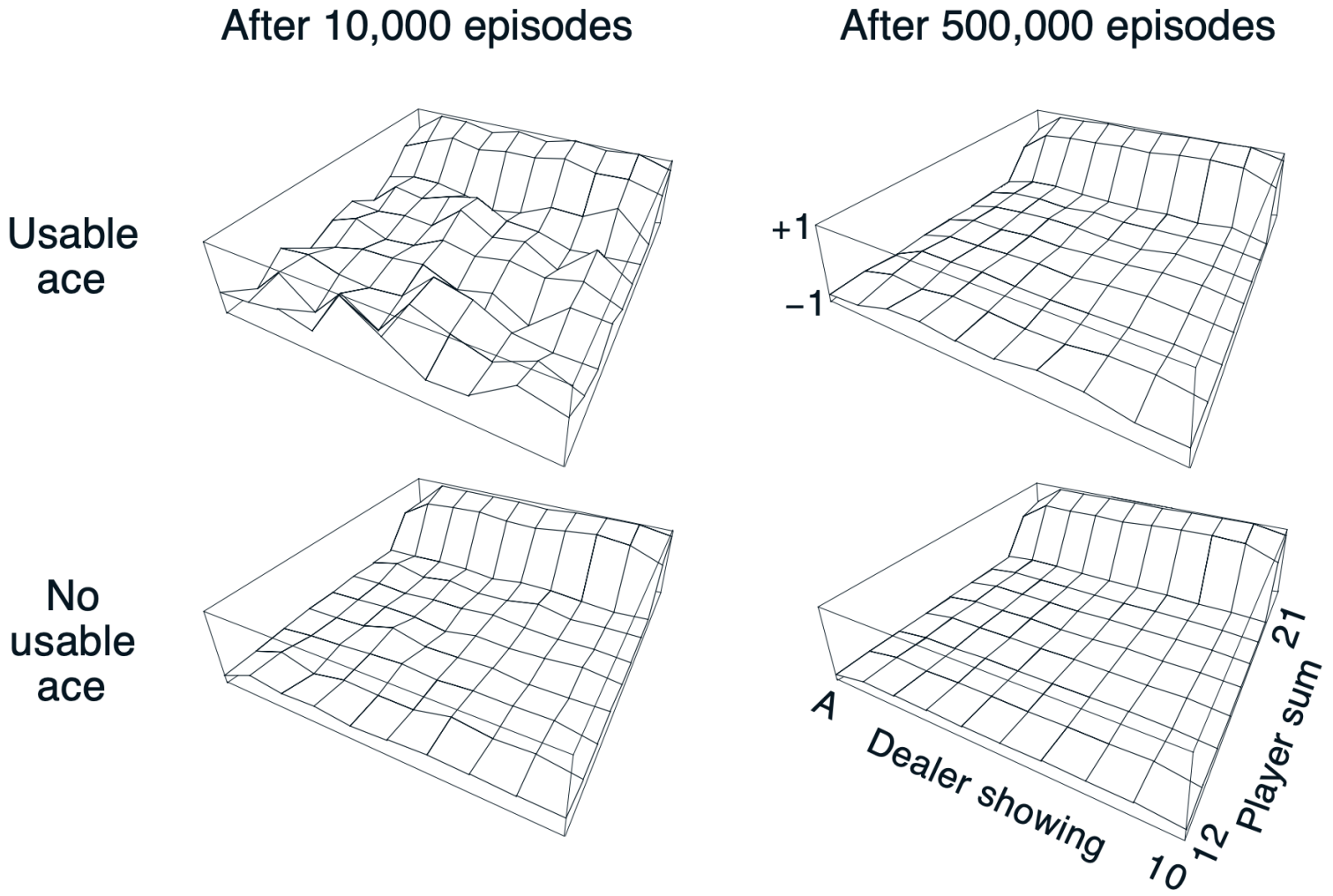
Every-visit

- To evaluate state x
- Every time-step t that state x is visited in an episode
- Increment counter $N(x) \leftarrow N(x) + 1$
- Increment total return $S(x) \leftarrow S(x) + G_t$
- Value is estimated by mean return $\hat{V}(x) = S(x)/N(x)$
- By law of large numbers $\hat{V}(x) \rightarrow V_\pi(x)$ as $N(x) \rightarrow \infty$

Example: Blackjack

- States (200 possible states):
  - Current sum (12-21)
  - Dealer's showing card (ace-10)
  - Do I have a 'usable' ace (yes-no)
- Actions:
  - Stand: stop receiving cards (and terminate)
  - Hit: take another card (no replacement)
- Reward:
  - For stand:
    - +1 if sum of cards > sum of dealer cards
    - 0 if sum of cards = sum of dealer cards
    - -1 if sum of cards < sum of dealer cards
  - For hit:
    - -1 if sum of cards > 21 (and terminate)
    - 0 otherwise
- Transitions:
  - Automatically hit if sum of cards < 12
- Policy:
  - Stand if sum of cards ≥ 20, otherwise hit

Example: Blackjack



Questions:

1. Consider the diagrams on the right
   a. Why does the estimated value function jump up for the last two rows in the rear?

   b. Why does it drop off for the whole last row on the left?

Example: Blackjack

The mean $\mu_1, \mu_2, \ldots$ of a sequence $x_1, x_2, \ldots$ can be computed incrementally

$$\mu_k = \frac{1}{k}\sum_{j=1}^{k} x_j$$

$$= \frac{1}{k}\left(x_k + \sum_{j=1}^{k-1} x_j\right)$$

$$= \frac{1}{k}\left(x_k + (k-1)\mu_{k-1}\right)$$

$$= \mu_{k-1} + \frac{1}{k}\left(x_k - \mu_{k-1}\right)$$

- We incrementally update $\hat{V}(x)$ after every episode $\tau = (x_0, u_0, \ldots, x_N, u_N)$
- For each state x_t with return G_t

$$N\left(x_t\right) \leftarrow N\left(x_t\right) + 1$$

$$\hat{V}\left(x_t\right) \leftarrow \hat{V}\left(x_t\right) + \frac{1}{N\left(x_t\right)}\left(G_t - \hat{V}\left(x_t\right)\right)$$

- In non-stationary problems, it is often useful to track a running mean to forget old (and ultimately less relevant) episodes

$$\hat{V}\left(x_t\right) \leftarrow \hat{V}\left(x_t\right) + \alpha\left(G_t - \hat{V}\left(x_t\right)\right)$$

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The skeleton of an RL algorithm

Temporal-Difference Learning

- TD is a combination of Monte Carlo and Dynamic Programming ideas
- Like MC, TD is model-free: no knowledge of MDP transitions / rewards. TD can learn from experience
- Like DP, TD methods update estimates based in part on other learned estimates, without waiting for a final outcome (they bootstrap)
- TD updates a guess towards a guess

Temporal-Difference Learning

- To compare MC and TD, let us consider the task of learning V_π from experience under policy π
- Incremental every-visit Monte Carlo:
  - Update value $\hat{V}(x_t)$ toward *actual* return G_t

$$\hat{V}(x_t) \leftarrow \hat{V}(x_t) + \alpha\left(G_t - \hat{V}(x_t)\right)$$

- Temporal-difference algorithm:
  - Update value $\hat{V}(x_t)$ toward estimated return $R_t + \gamma\hat{V}(x_{t+1})$

$$\hat{V}(x_t) \leftarrow \hat{V}(x_t) + \alpha\left(R_t + \gamma\hat{V}(x_{t+1}) - \hat{V}(x_t)\right)$$

  - $R_t + \gamma\hat{V}(x_{t+1})$ is called TD target
  - $\delta_t = R_t + \gamma\hat{V}(x_{t+1}) - \hat{V}(x_t)$ is called TD error

TD methods combine:

1) the sampling of Monte Carlo
2) with the bootstrapping of DP

Advantages and disadvantages of MC vs TD

- TD can learn *before* knowing the final outcome
  - TD can learn online after every step
  - MC must wait until the end of the episode

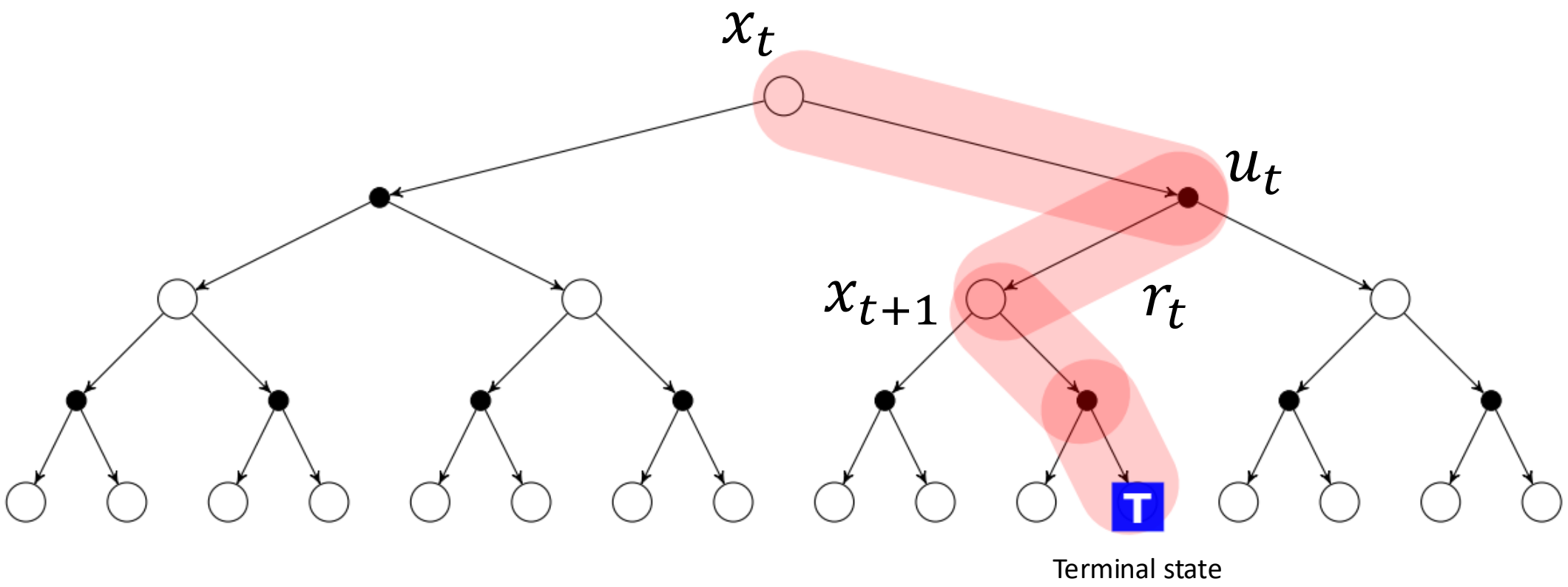
- TD can learn without the final outcome
  - TD can learn from incomplete sequences
  - MC can only learn from complete sequences
  - TD works in continuing (non-terminating) environments
  - MC only works in episodic (terminating) environments

Bias-Variance Trade-off

- Return $G_t = R_{t+1} + \gamma R_{t+2} + \cdots + \gamma^{T-1} R_T$ is an unbiased estimate of $V_\pi(x)$
- In theory, the *true* TD target $R_t + \gamma V(x_{t+1})$ is also an unbiased estimate of $V_\pi(x)$
- TD target $R_t + \gamma \hat{V}(x_{t+1})$is a biased estimate of $V_\pi(x)$
- However, the TD target is much lower variance than the return
  - The return G_t depends on a full sequence of random actions, transitions, rewards (i.e., evaluated at the end of the episode)
  - The TD error only depends on one random action, transition, reward

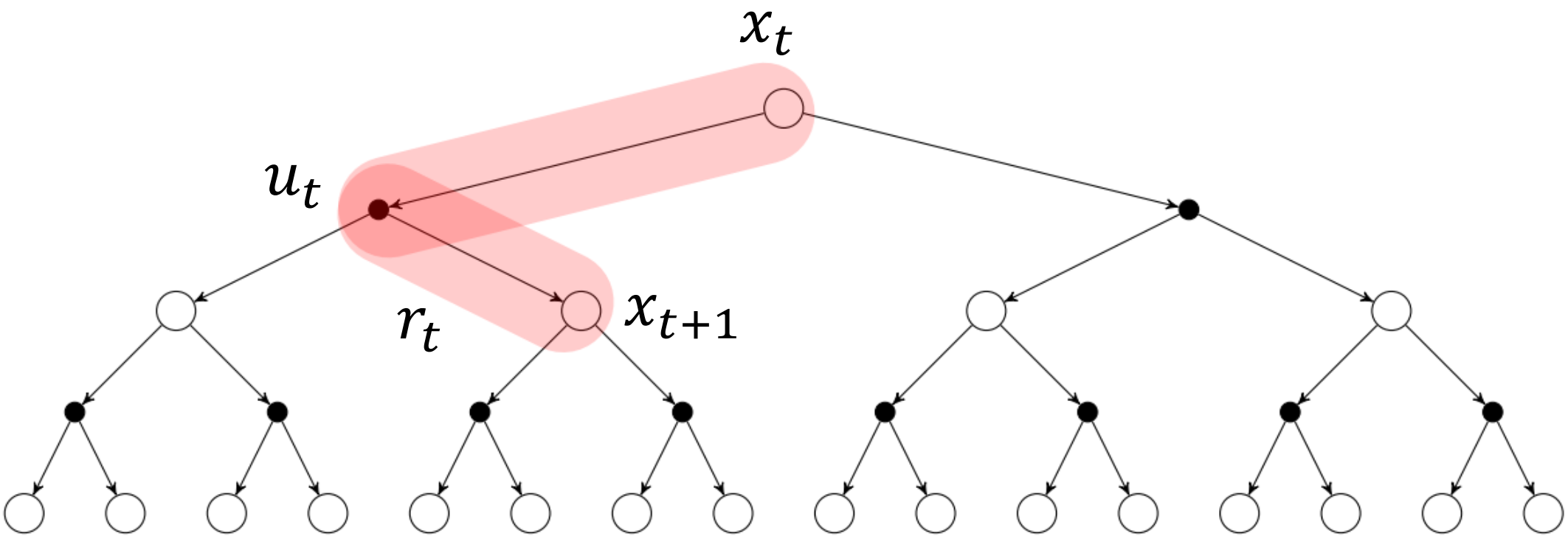
Monte-Carlo Backup

$$\hat{V}(x_t) \leftarrow \hat{V}(x_t) + \alpha\left(G_t - \hat{V}(x_t)\right)$$



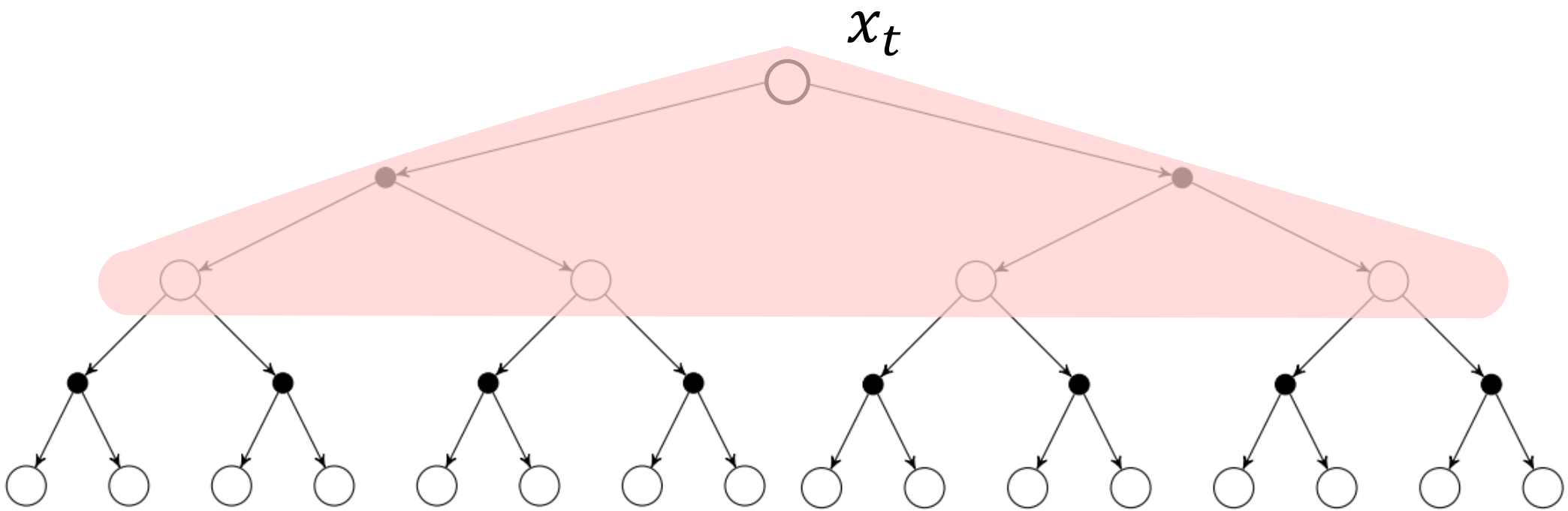
Temporal-Difference Backup

$$\hat{V}(x_t) \leftarrow \hat{V}(x_t) + \alpha\left(R_t + \gamma\hat{V}(x_{t+1}) - \hat{V}(x_t)\right)$$



Dynamic Programming Backup

$$\hat{V}(x_t) \leftarrow \mathbb{E}\left[R_t + \gamma \hat{V}(x_{t+1})\right]$$

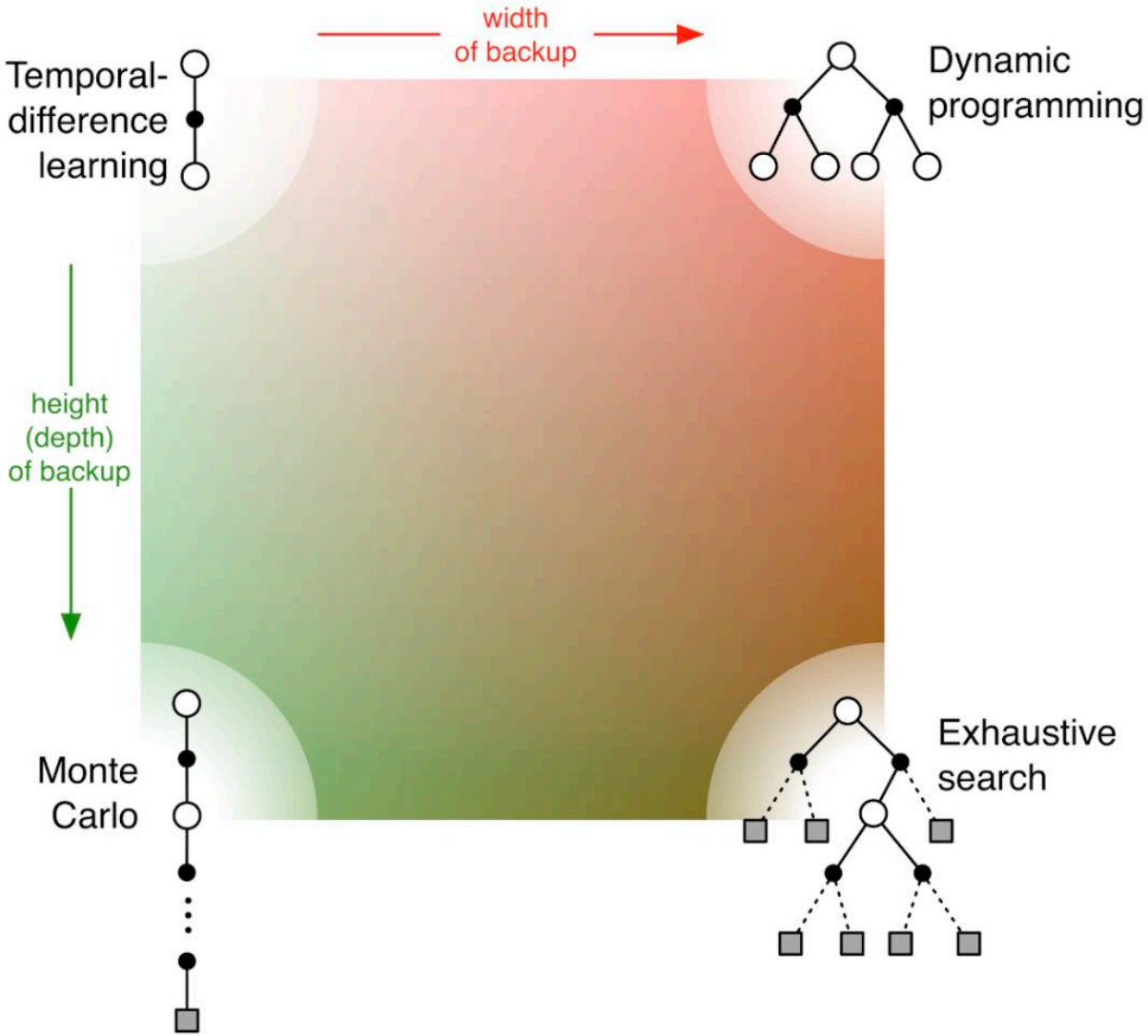


Bootstrapping and sampling

- Sampling: define the update through samples to approximate expectations
  - MC samples
  - TD samples
  - DP does not sample

- Bootstrapping: define the update through an estimate
  - MC does not bootstrap
  - TD bootstraps
  - DP bootstraps

A unifying view of RL



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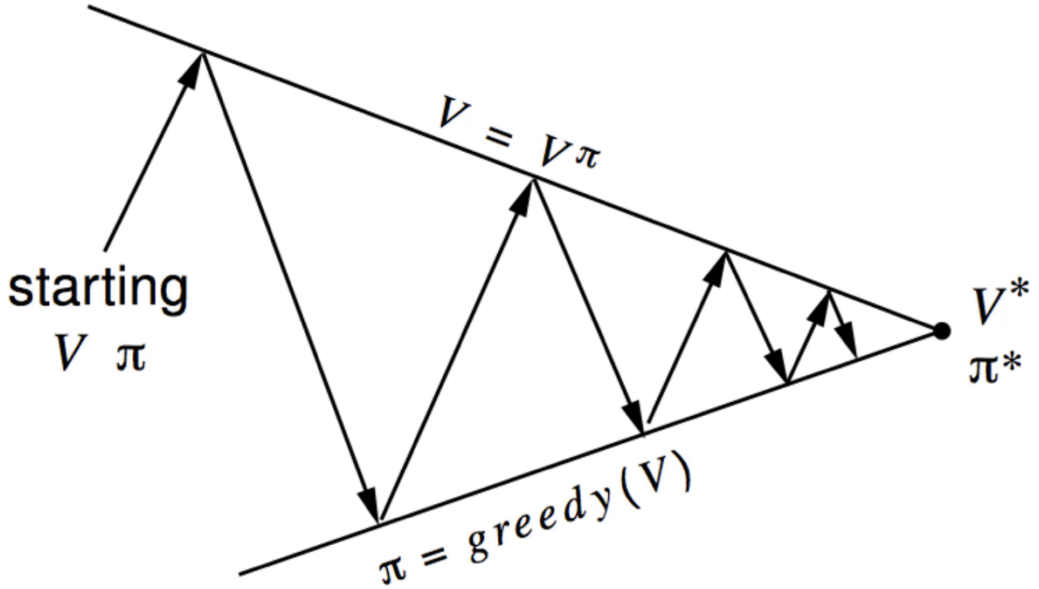
Generalized Policy Iteration

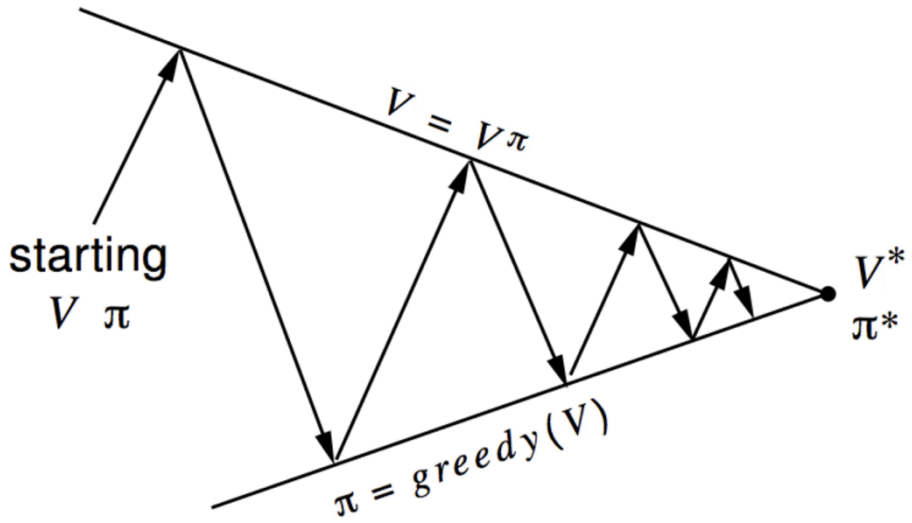
In previous lectures, we discussed Policy Iteration as consisting of two simultaneous, interactive processes: Policy Evaluation and Policy Improvement

We use the term *generalized policy iteration* (GPI) to refer to the general idea of letting policy-evaluation and policy improvement processes interact, independent of the granularity and other details of the two processes.



Policy Evaluation: Iterative policy evaluation
Policy Improvement: Greedy policy improvement

GPI with Monte-Carlo Evaluation



Policy Evaluation: Monte-Carlo policy evaluation of $V(x)$?

Policy Improvement: Greedy policy improvement?

Problem:

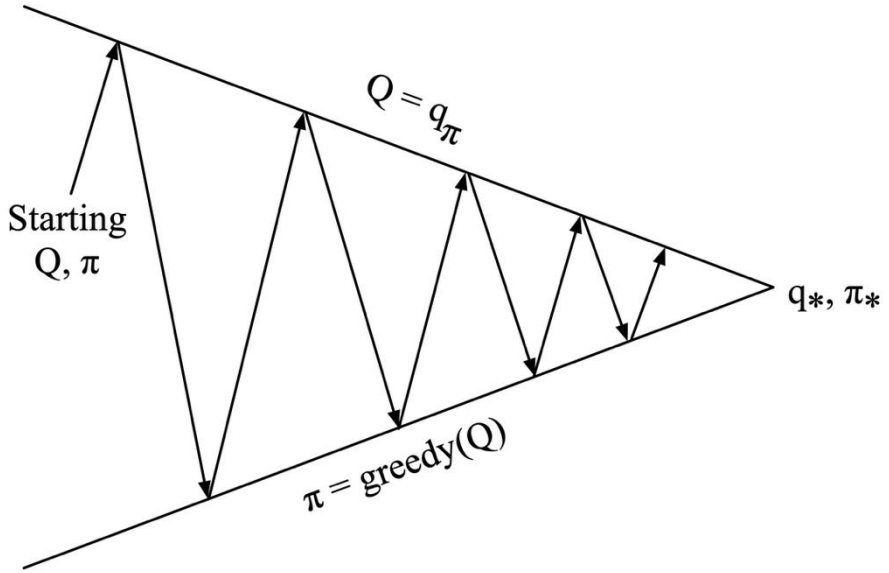
Greedy policy improvement over $V(x)$ requires a model of the MDP!

$$\pi_{k+1}(x) = \arg\max_u \left(R(x,u) + \gamma \sum_{x_{t+1} \in \mathcal{X}} T(x_{t+1} \mid x_t, u_t) V_{k+1}(x_{t+1}) \right)$$

On the other hand, greedy policy improvement over $Q(x,u)$ does not

$$\pi_{k+1}(x) = \arg\max_u Q(x,u)$$

GPI with state-action value function



Policy Evaluation: Monte-Carlo policy evaluation of $Q(x, u)$

Policy Improvement: Greedy policy improvement?

Problem:

Exploration! Let's consider an example:

- Need to choose among two possible doors:
- You open the left door: $R = 0, Q(x, left) = 0$
- You open the right door: $R = 1, Q(x, right) = 1$
- You open the right door: $R = 3, Q(x, right) = 2$
- You open the right door: $R = 2, Q(x, right) = 2$
- …

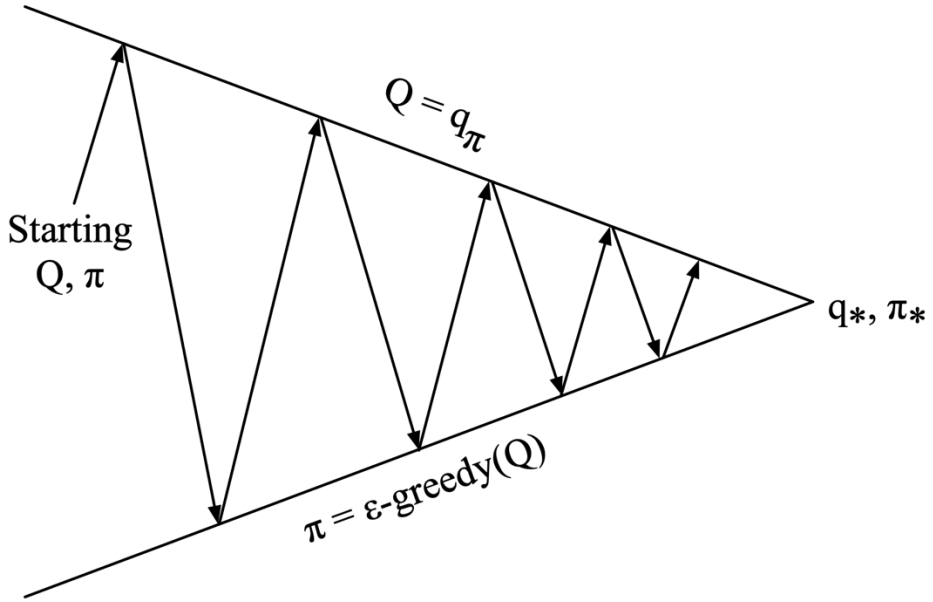
To estimate state-action values through samples, every state-action pair needs to be visited (opposed to each state as in MC estimation of $V(x)$)

Deterministic policies do not allow this exploration

A simple (but effective) strategy: ϵ-Greedy Exploration

- With probability $1 - \epsilon$, choose the greedy action
- With probability ϵ, choose a random action
- Ensures that all m actions are tried with non-zero probability

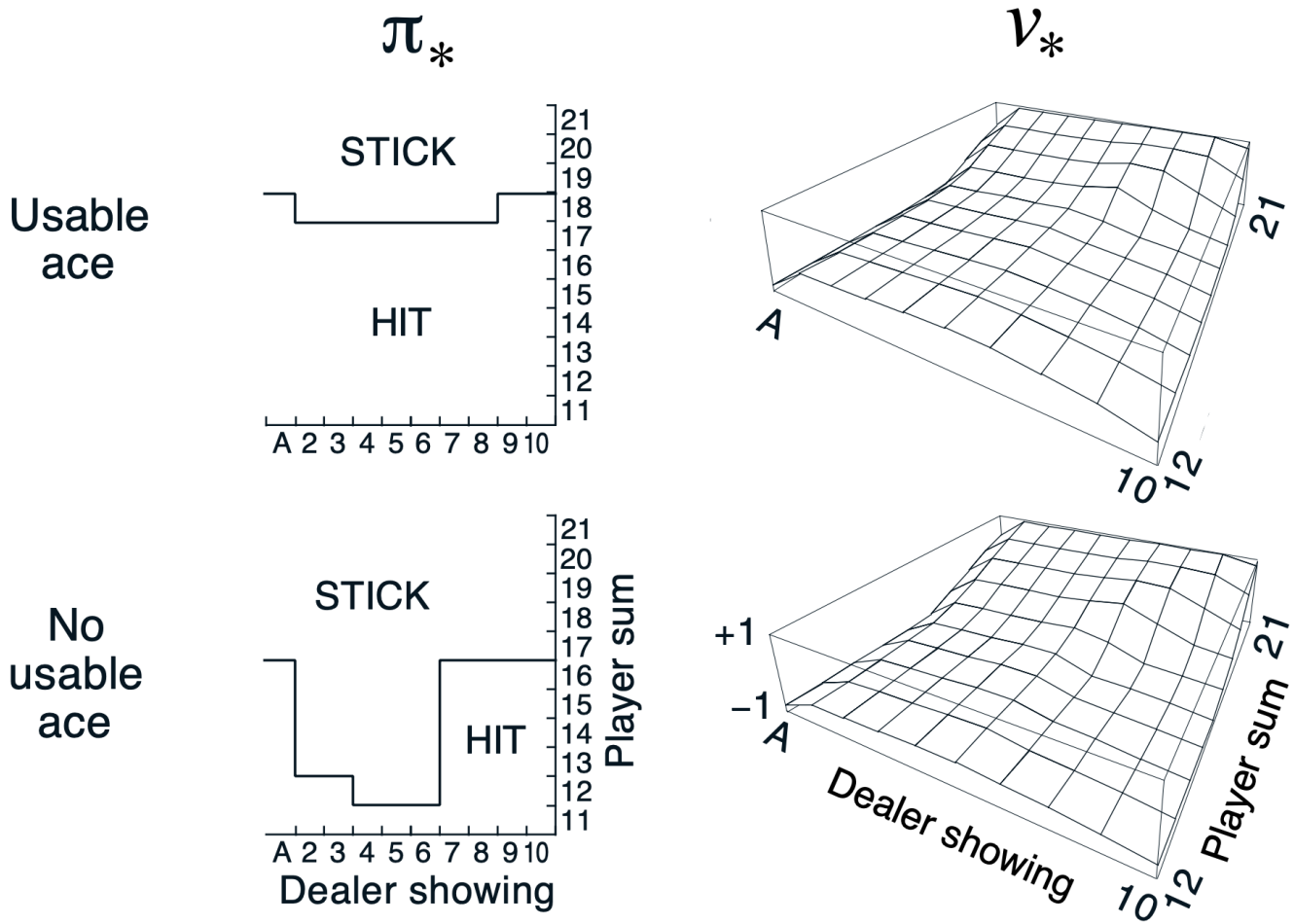
$$\pi(u \mid x) = \begin{cases} \frac{\epsilon}{m} + 1 - \epsilon & \text{if } u^* = \underset{u \in \mathcal{U}}{\operatorname{argmax}}\, Q(x, u) \\ \frac{\epsilon}{m} & \text{otherwise} \end{cases}$$



Policy Evaluation: Monte-Carlo policy evaluation of $Q(x, u)$

Policy Improvement: ϵ-Greedy policy improvement?

Example: Blackjack



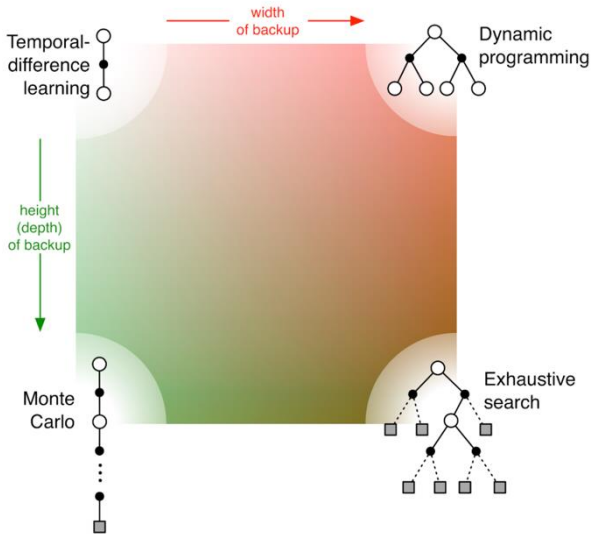
To recap…

We discussed the main limitations of exact methods (such as Policy/Value Iteration):

- Update equations (i.e., Bellman equations) require access to dynamics model $T(x_{t+1} \mid x_t, u_t)$ Sampling-based approximations
- Iteration over (and storage of) all states and actions requires small, discrete state-action space Function approximation

We introduced core ideas such as Monte-Carlo and Temporal-Difference Learning and derived ways to solve unknown MDPs

However, we did not discuss methods to deal with high-dimensional state/action spaces… more on this later!



Outline

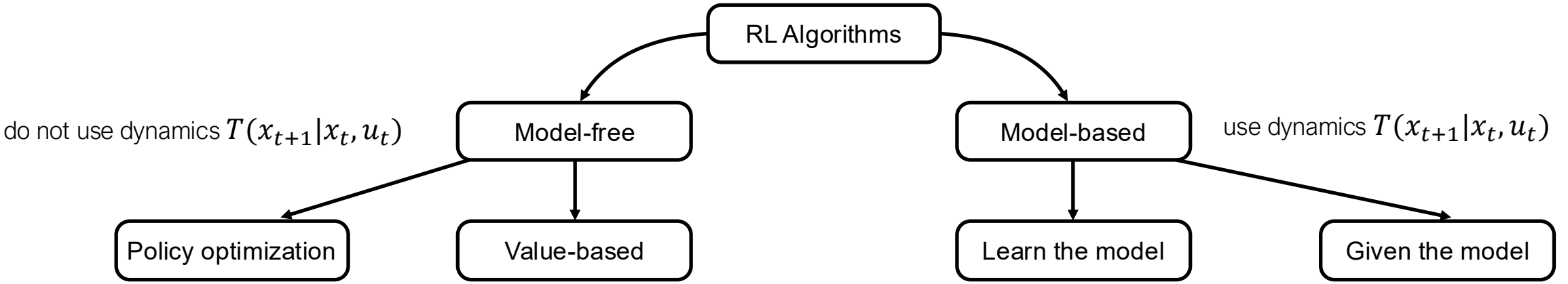
Recap: The RL problem

From exact methods to model-free control

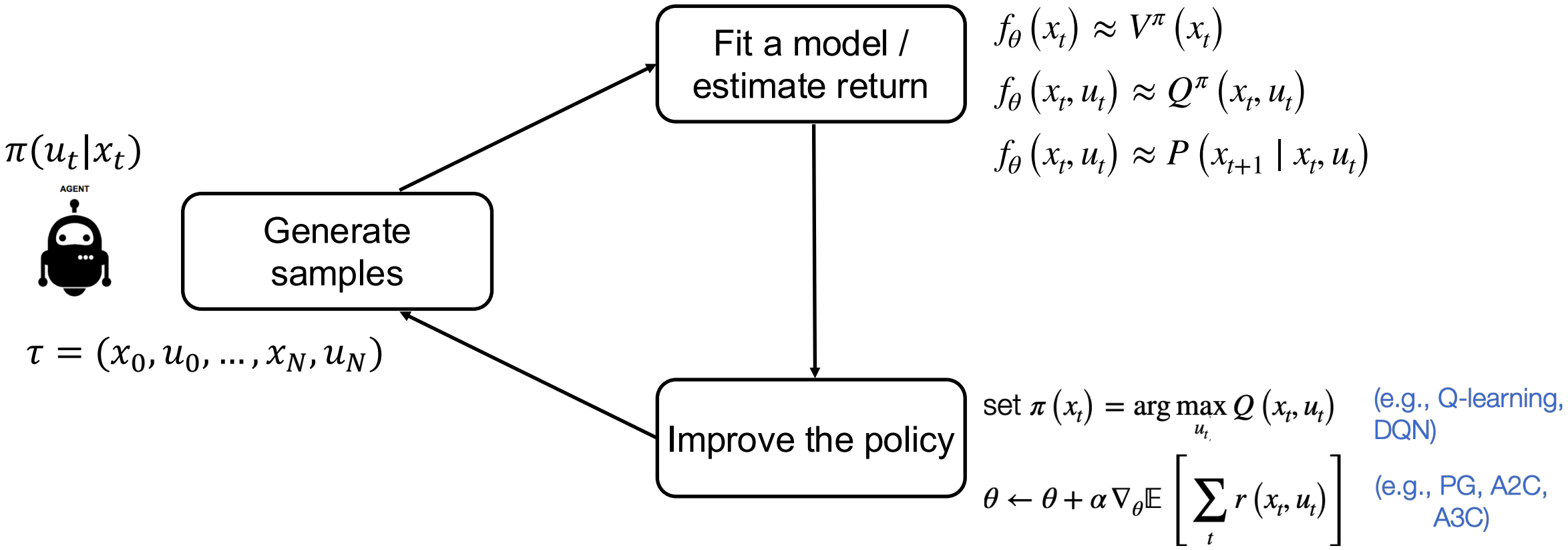
- Monte Carlo Learning
- Temporal-Difference (TD) Learning

The skeleton of an RL algorithm

A taxonomy of RL



The skeleton of an RL algorithm



Next time

- Value-based RL