CS 277: Control and Reinforcement Learning

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Lecture 15: Control as Inference

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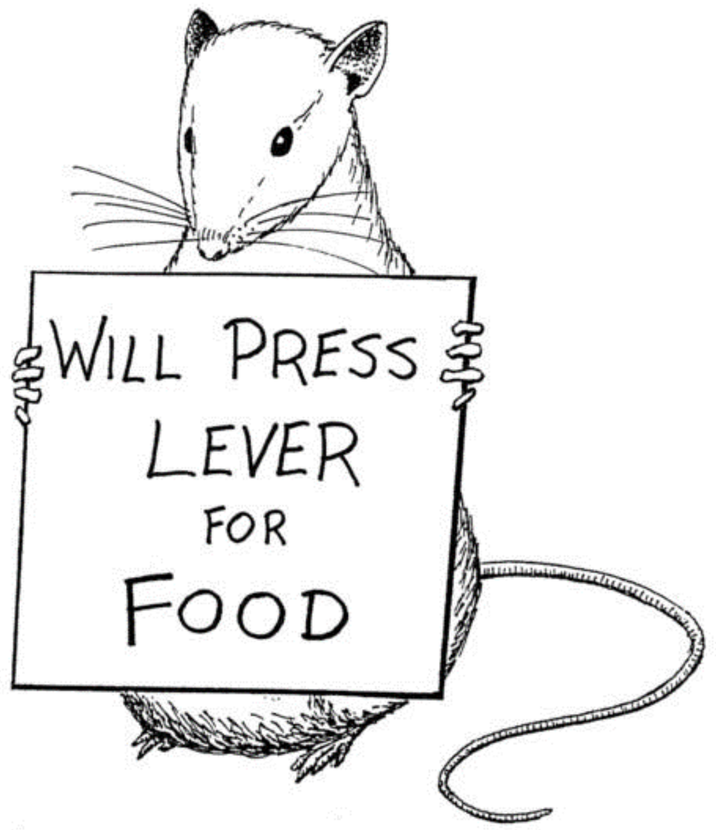

Today's lecture

Linearly Solvable MDPs

Bounded RL

SQL, SAC

Bounded optimality

- Bounded optimizer = trades off value and divergence from prior $\pi_0(a \mid s)$

$$\max_\pi \mathbb{E}_{s,a\sim p_\pi}[r(s,a)] - \tau \mathbb{D}[\pi \| \pi_0] = \max_\pi \mathbb{E}_{s,a\sim p_\pi}\left[\beta r(s,a) - \log \frac{\pi(a \mid s)}{\pi_0(a \mid s)}\right]$$

- $\beta = \frac{1}{\tau}$ is the tradeoff coefficient between value and relative entropy
  - Similar to the inverse-temperature in thermodynamics
  - As $\beta \to 0$, the agent will fall back to the prior $\pi \to \pi_0$
  - As $\beta \to \infty$, the agent will be a perfect value optimizer $\pi \to \pi^*$
- We'll see reasons to have finite β

Simplifying assumption

- MaxEnt IRL was approximate because it violated dynamical constraints
  - $p_\pi(\xi) \propto \exp(R(\xi))$ (regardless of trajectory feasibility)
- For simplicity, let's do the same for RL
  - Suppose the environment is fully controllable $s_{t+1} = a_t$
  - Bellman equation:

$$V^*_\beta(s) = \max_\pi \mathbb{E}_{s'|s\sim\pi}\left[r(s) - \frac{1}{\beta}\log\frac{\pi(s'|s)}{\pi_0(s'|s)} + \gamma V^*_\beta(s')\right]$$

$$= r(s) - \frac{1}{\beta}\min_\pi \mathbb{D}\left[\pi \,\middle\|\, \frac{\pi_0(s'|s)\exp(\beta\gamma V^*_\beta(s'))}{Z'_\beta(s)}\right] + \frac{1}{\beta}\log Z'_\beta(s)$$

Soft-greedy policy

- To solve the Bellman recursion

$$V_\beta^*(s) = \max_\pi \mathbb{E}_{s'|s\sim\pi}\left[r(s) - \frac{1}{\beta}\log\frac{\pi(s'|s)}{\pi_0(s'|s)} + \gamma V_\beta^*(s')\right]$$

$$= r(s) - \frac{1}{\beta}\min_\pi \mathbb{D}\left[\pi \,\middle\|\, \frac{\pi_0(s'|s)\exp(\beta\gamma V_\beta^*(s'))}{Z'_\beta(s)}\right] + \frac{1}{\beta}\log Z'_\beta(s)$$

  - Differentiate, with λ_s constraining $\sum_{s'} \pi(s'|s) = 1$

$$0 = \nabla_{\pi(s'|s)}\mathbb{E}_{s'|s\sim\pi}\left[-\frac{1}{\beta}\log\frac{\pi(s'|s)}{\pi_0(s'|s)} + \gamma V_\beta^*(s') - \lambda_s\right]$$

$$= -\frac{1}{\beta}\log\frac{\pi(s'|s)}{\pi_0(s'|s)} + \gamma V_\beta^*(s') - \lambda_s - \pi(s'|s)\,\nabla_{\pi(s'|s)}\log\pi(s'|s)$$

- Soft-greedy policy: $\pi_\beta^*(s'|s) \propto \pi_0(s'|s)\exp(\beta\gamma V_\beta^*(s'))$ (more general form later)

Linearly-Solvable MDPs (LMDPs)

- Plugging the soft-greedy policy back into the value recursion:

$$V_\beta^*(s) = r(s) - \frac{1}{\beta} \min_\pi \mathscr{D}\left[\pi \,\middle\|\, \frac{\pi_0(s'|s)\exp(\beta\gamma V_\beta^*(s'))}{Z'_\beta(s)} + \frac{1}{\beta}\log Z'_\beta(s)\right]$$

$$= r(s) + \frac{1}{\beta}\log Z'_\beta(s) = r(s) + \frac{1}{\beta}\log \mathbb{E}_{s'|s\sim\pi_0}[\exp(\beta\gamma V_\beta^*(s'))]$$

- Alternatively:

$$Z_\beta(s) = \exp(\beta V_\beta^*(s)) = \exp(\beta r(s)) Z'_\beta(s) = \exp(\beta r(s))\mathbb{E}_{s'|s\sim\pi_0}[Z_\beta^\gamma(s')]$$

- In the undiscounted case $\gamma = 1$, with $D = \operatorname{diag}(\exp \beta r)$: $z = DP_0 z$

- We can solve for z, and therefore π, by finding a right-eigenvector of DP_0

Z-learning

$$Z(s) = \exp(\beta r(s))\mathbb{E}_{s'|s\sim\pi_0}[Z^\gamma(s')]$$

- We can do the same model-free:
  - Given experience (s, r, s') sampled by the prior policy π_0
  - Update $Z_\beta(s) \to \exp \beta r Z^\gamma(s')$
- Full-controllability condition ($s_{t+1} = a_t$) can be relaxed to allow $\pi_0(s' \mid s) = 0$
  - But we still allow any transition distribution $\pi(s' \mid s)$ over the remaining support
  - Later: the general case, $p(s' \mid s) = \sum_a \pi(a \mid s) p(s' \mid s, a)$

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Duality between value and log prob

- We've seen many cases where log-probs play the role of reward / value
  - Or values the role of logits (unnormalized log-probs)
- Examples:
  - In LQG, $\log p(x|\hat{x}) = -\frac{1}{2}x^\intercal \Sigma x + \text{const}$; costs / values are quadratic
  - In value-based algorithms, a good exploration policy is $\pi(a|s) = \underset{a}{\text{sm}}\, \beta Q(s,a)$
  - Imitation Learning can be viewed as RL with $r(s,a) = \log \pi_T(a|s)$
  - In IRL, a reward function can be viewed as a discriminator $D(s) = \exp r(s)$
  - etc.

Full-controllability duality

$$Z(s) = \exp(\beta r(s))\, \mathbb{E}_{s'|s \sim \pi_0}[Z^\gamma(s')]$$

- Backward filtering in a partially observable system with dynamics $\pi_0(s'|s)$

$$p(o_{\geqslant t}|s_t) = p(o_t|s_t)\, \mathbb{E}_{s_{t+1}|s_t \sim \pi_0}[p(o_{\geqslant t+1}|s_{t+1})]$$

- Equivalent if $r(s) = p(o|s)$ and $Z(s) = p(o_{\geqslant t}|s_t)$
  - With the actual observations that we see

- Can we say anything about the partially controllable case?

Bounded RL

- Back to the general case: $\max_\pi \mathbb{E}_{s,a\sim p_\pi}[\beta r(s,a)] - \mathbb{D}[\pi\|\pi_0]$

- Define an entropy-regularized Bellman optimality operator

$$\mathcal{B}[V](s) = \max_\pi \mathbb{E}_{a|s\sim\pi}\left[r(s,a) - \frac{1}{\beta}\log\frac{\pi(a|s)}{\pi_0(a|s)} + \gamma\,\mathbb{E}_{s'|s,a\sim p}[V(s')]\right]$$

  - As in the unbounded case $\beta \to \infty$, this operator is contracting

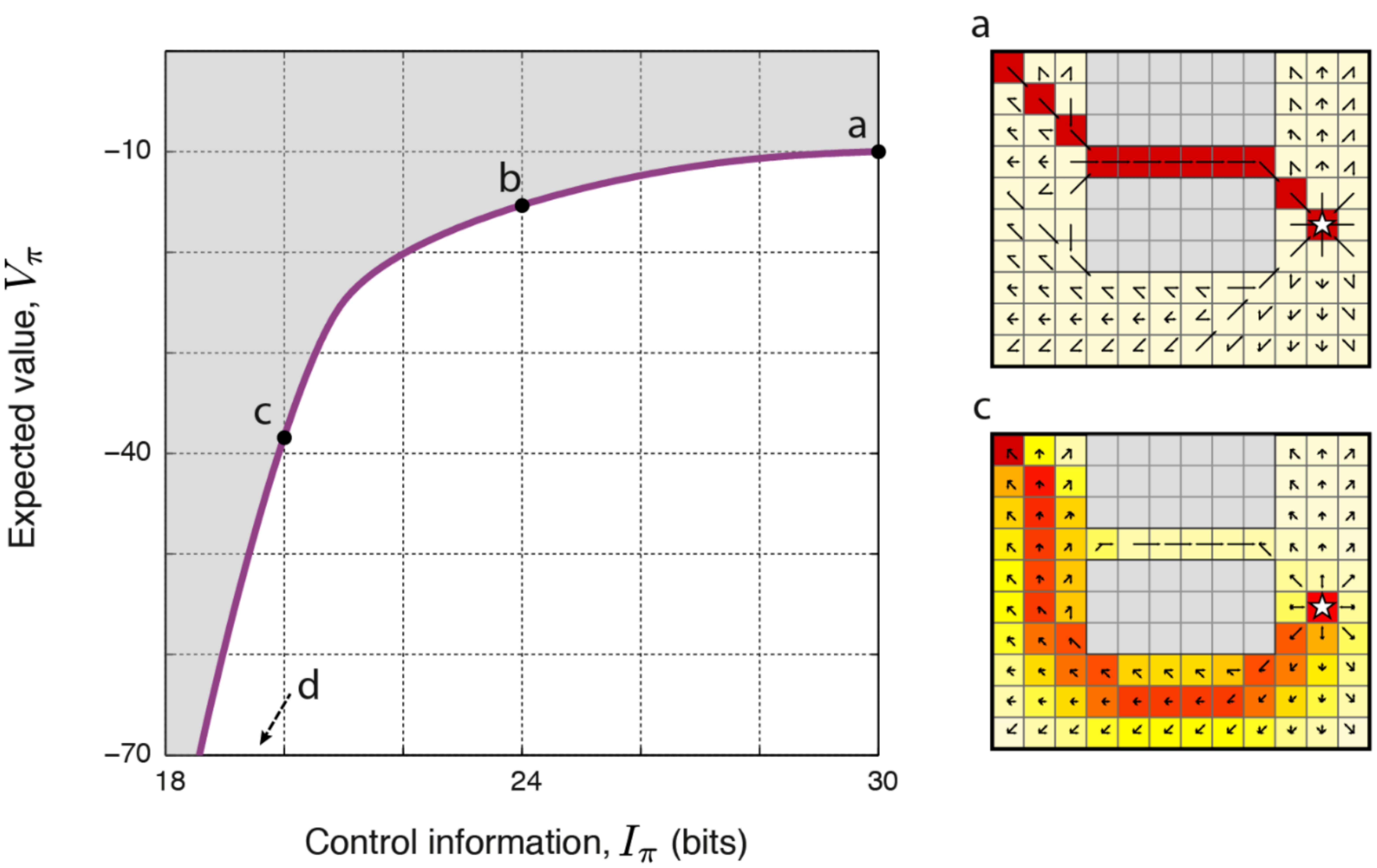
- Optimal policy:

$$\pi(a|s) \propto \pi_0(a|s)\exp\beta(r(s,a) + \gamma\,\mathbb{E}_{s'|s,a\sim p}[V(s')]) = \pi_0(a|s)\exp\beta Q(s,a)$$

- Optimal value recursion:

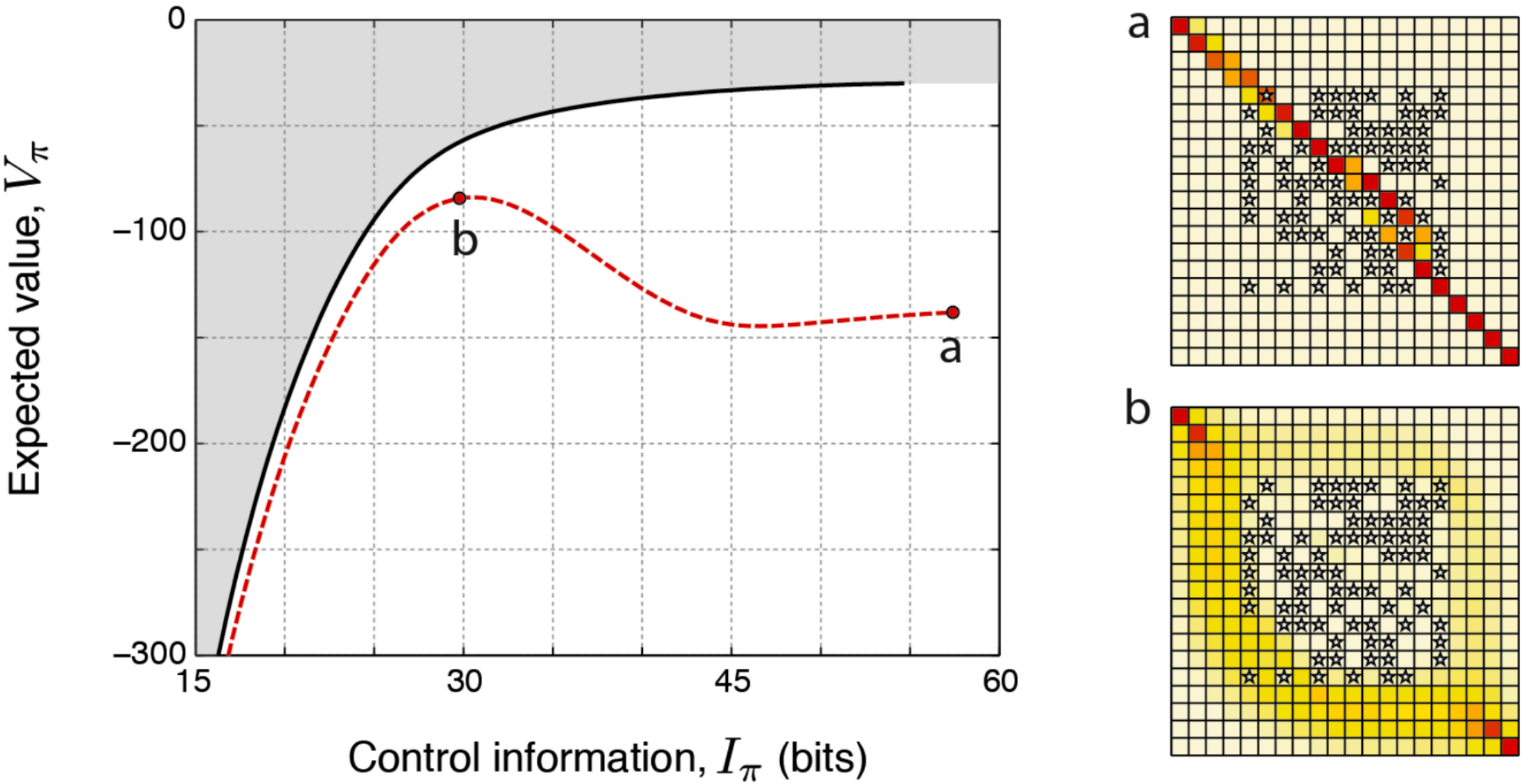
$$V(s) = \frac{1}{\beta}\log Z(s) = \frac{1}{\beta}\log\mathbb{E}_{a|s\sim\pi_0}[\exp\beta(r(s,a) + \gamma\,\mathbb{E}_{s'|s,a\sim p}[V(s')])]$$

Value–RelEnt curve



[Rubin et al., 2012]

Robustness to model uncertainty



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Exact and approximate inference

- Suppose we want to max log-likelihood of a dataset $\max_\theta \mathbb{E}_{x\sim\mathcal{D}}[\log p_\theta(x)]$
  - And computing it is easier with a latent intermediate variable $p_\theta(z)p_\theta(x|z)$
- Expectation–Gradient (EG):

$$\nabla_\theta \log p_\theta(x) = \mathbb{E}_{z|x\sim p_\theta}[\nabla_\theta \log p_\theta(z,x)]$$

- But what if sampling from the exact posterior $p_\theta(z|x)$ is also hard?
- Let's do importance sampling from any approximate posterior $q_\phi(z|x)$

$$\log p_\theta(x) = \log \mathbb{E}_{z|x\sim q_\phi}\left[\frac{p_\theta(z)}{q_\phi(z|x)}p_\theta(x|z)\right] \geqslant \mathbb{E}_{z|x\sim q_\phi}\left[\log \frac{p_\theta(z,x)}{q_\phi(z|x)}\right]$$

Variational Inference (VI): Evidence Lower Bound (ELBO)

- Two ways of decomposing $p_\theta(z, x)$:

$$\log p_\theta(x) \geqslant -\mathbb{D}[q_\phi(z|x) \| p_\theta(z, x)]$$
$$= \log p_\theta(x) + \mathbb{E}_{z|x \sim q_\phi}\left[\log \frac{p_\theta(z|x)}{q_\phi(z|x)}\right] \qquad (1)$$
$$= \mathbb{E}_{z|x \sim q_\phi}\left[\log \frac{p_\theta(z)}{q_\phi(z|x)} + \log p_\theta(x|z)\right] \qquad (2)$$

- (1) shows that the bounding gap is $\mathbb{D}[q_\phi(z|x) \| p_\theta(z|x)] \geqslant 0$
    - It is smaller the better we can approximate $p_\theta(z|x)$ using $q_\phi(z|x)$
- (2) shows how the bound can be computed efficiently
    - We can use it as a proxy for our objective

Control as inference

- Consider soft "success" indicators

$$p(v_t = 1 | s_t, a_t) = \exp \beta r(s_t, a_t)$$

- What is the log-probability that an entire trajectory ξ "succeeds"?

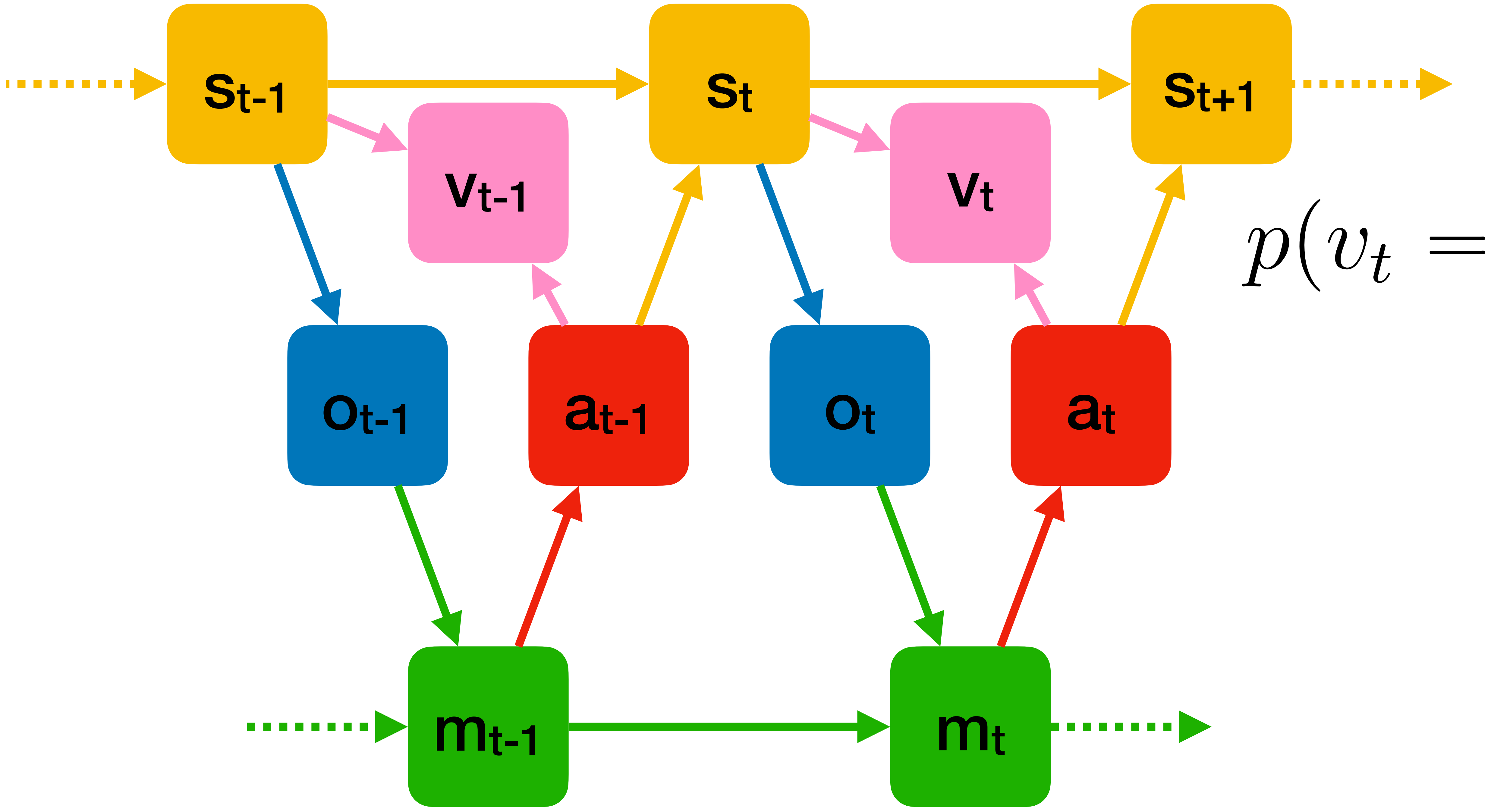
$$\log p(\mathcal{V} | \xi) = \sum_t \log p(v_t = 1 | s_t, a_t) = \beta \sum_t r(s_t, a_t) = \beta R$$

- What is the posterior distribution over trajectories, given success?

$$p(\xi | \mathcal{V}) = \frac{p_0(\xi) p(\mathcal{V} | \xi)}{p_0(\mathcal{V})} = \frac{p_0(\xi) \exp \beta R}{Z}$$

- But this distribution is not realizable, due to dynamical constraints

Pseudo-observations



$$p(v_t = 1 | s_t, a_t) = \exp \beta r_t$$

General duality between VI and bounded RL

- Take $x = \mathcal{V}$, $z = \xi$, and $p_\theta(\xi) = p_0(\xi)$
- Optimize the ELBO with a realizable proposal distribution $q_\phi(\xi|\mathcal{V}) = p_{\pi_\phi}(\xi)$
- The ELBO becomes

$$\mathbb{E}_{\xi|\mathcal{V}\sim q_\phi}\left[\log p_0(\mathcal{V}|\xi) + \log \frac{p_0(\xi)}{q_\phi(\xi|\mathcal{V})}\right] = \mathbb{E}_{\xi\sim p_{\pi_\phi}}\left[\beta R - \log \frac{p_{\pi_\phi}(\xi)}{p_0(\xi)}\right]$$
$$= \mathbb{E}_{s,a\sim p_{\pi_\phi}}\left[\beta r(s,a) - \log \frac{\pi_\phi(a|s)}{\pi_0(a|s)}\right]$$

  - Equivalent to the bounded RL problem!

Soft Q-Learning (SQL)

- TD off-policy algorithm for model-free bounded RL

- With tabular parametrization:

$$\Delta Q(s,a) = r + \frac{\gamma}{\beta} \log \mathbb{E}_{a'|s' \sim \pi_0}[\exp \beta Q(s',a')] - Q(s,a)$$

- With differentiable parametrization:

$$\mathcal{L}_\theta(s,a,r,s') = \left(r + \frac{\gamma}{\beta} \log \mathbb{E}_{a'|s' \sim \pi_0}[\exp \beta Q_{\bar{\theta}}(s',a')] - Q_\theta(s,a) \right)^2$$

- As $\beta \to \infty$, this becomes (Deep) Q-Learning

Soft Actor–Critic (SAC)

- AC off-policy algorithm for model-free bounded RL

- Optimally:

$$\pi(a|s) = \frac{\pi_0(a|s)\exp \beta Q(s,a)}{\exp \beta V(s)} \qquad \forall a: \; V(s) = Q(s,a) - \frac{1}{\beta}\log\frac{\pi(a|s)}{\pi_0(a|s)}$$

- We can train the critic off-policy

$$\mathcal{L}_\phi(s,a,r,s',a') = \left(r + \gamma\left(Q_{\bar\phi}(s',a') - \frac{1}{\beta}\log\frac{\pi_\theta(a'|s')}{\pi_0(a'|s')}\right) - Q_\phi(s,a)\right)^2$$

- And the actor to be soft-greedy = distill / imitate the critic

$$\mathcal{L}_\theta(s) = \mathbb{E}_{a|s\sim\pi_\theta}[\log \pi_\theta(a|s) - \log \pi_0(a|s) - \beta Q_\phi(s,a)]$$

- Allows continuous action spaces

Why use a finite β

- Model suboptimal agents / teachers
- Robustness to model misspecification / avoid overfitting
- Eliminate bias due to winner's curse
  - For $\beta \to \infty$ $\qquad \mathbb{E}[\max_a Q(a)] \geqslant \max_a \mathbb{E}[Q(a)]$
  - For $\beta \to 0$ $\qquad \mathbb{E}[\mathbb{E}_{a\sim\pi_0}[Q(a)]] = \mathbb{E}_{a\sim\pi_0}[\mathbb{E}[Q(a)]] \leqslant \max_a \mathbb{E}[Q(a)]$
  - Somewhere in between there must be an unbiased β
- More reasons...

Recap

- Duality: rewards and values are like log-probs
- Can use inference methods to plan and learn
- Fall back to “optimal” methods in the 0-temperature case
- But many reasons to keep finite temperature, during training and often after