CS 277: Control and Reinforcement Learning

Winter 2022

Lecture 2: Imitation Learning

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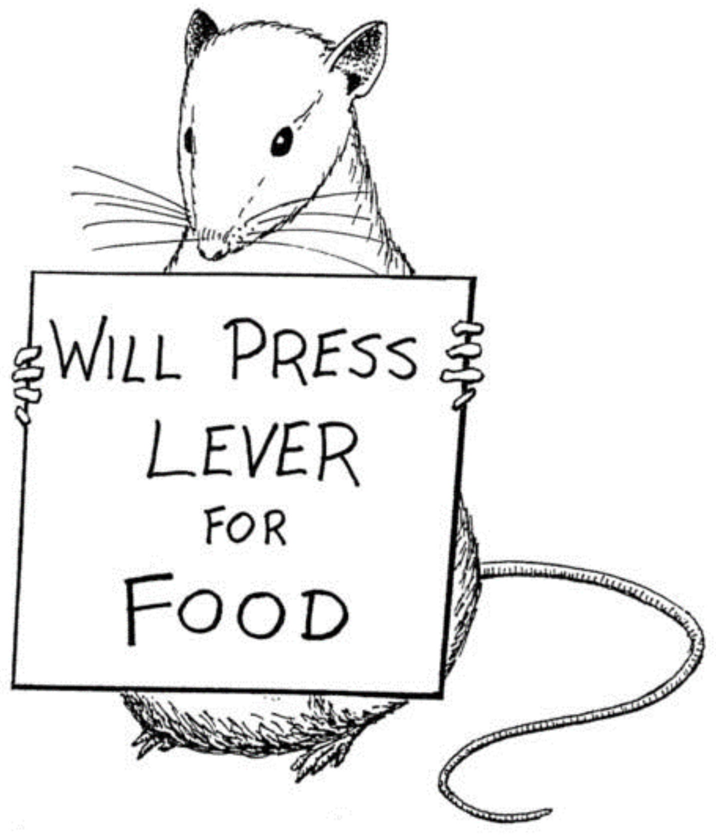


Logistics

logistics

- Follow announcements and discussions on ed
- See website for schedule, recordings, resources, etc.

assignments

- Quiz 1 due this Friday
- Assignment 1 to be published soon

Imitation Learning (IL)

- How can we teach an agent to perform a task?
- Often there is an expert that already knows how to perform the task
  - A human operator who controls a robot
  - A black-box artificial agent that we can observe but not copy
  - An agent with different representation or embodiment

- The expert can demonstrate the task to create a training dataset $\mathscr{D} = \{\xi^{(i)}\}_i$
  - Each demonstration is a trajectory $\xi = s_0, a_0, s_1, a_1, \ldots$
  - Then the learner imitates these demonstrations

IL = Learning from Demonstrations (LfD)

- Teacher provides demonstration trajectories $\mathscr{D} = \{\xi^{(1)}, \ldots, \xi^{(m)}\}$
- Learner trains a policy π_θ to minimize a loss $\mathscr{L}(\theta)$
- For example, negative log-likelihood (NLL):

$$\arg\min_\theta \mathscr{L}_\theta(\xi) = \arg\min_\theta(-\log p_\theta(\xi))$$

$$= \arg\max_\theta \left(\log p(s_0) + \sum_{t=0}^{T-1} \log \pi_\theta(a_t | s_t) + \log p(s_{t+1} | s_t, a_t) \right)$$

$$= \arg\max_\theta \sum_{t=0}^{T-1} \log \pi_\theta(a_t | s_t)$$

model-free
= no need to know the environment dynamics p

Today's lecture

Behavior Cloning

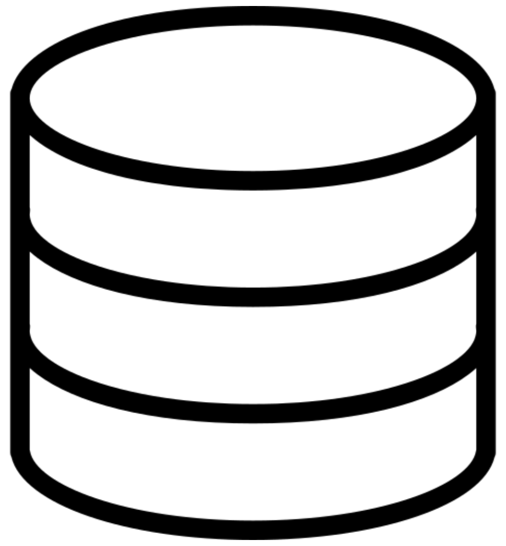
Better behavior modeling

Alleviating train–test mismatch

Behavior Cloning (BC)

- Behavior Cloning:
  - Break down trajectories $\{\xi^{(1)}, \ldots, \xi^{(m)}\}$ into steps $\{(s_0^{(1)}, a_0^{(1)}), \ldots, (s_{T_m-1}^{(m)}, a_{T_m-1}^{(m)})\}$
  - Train $\pi_\theta : s \mapsto a$ using supervised learning

observations
+
actions



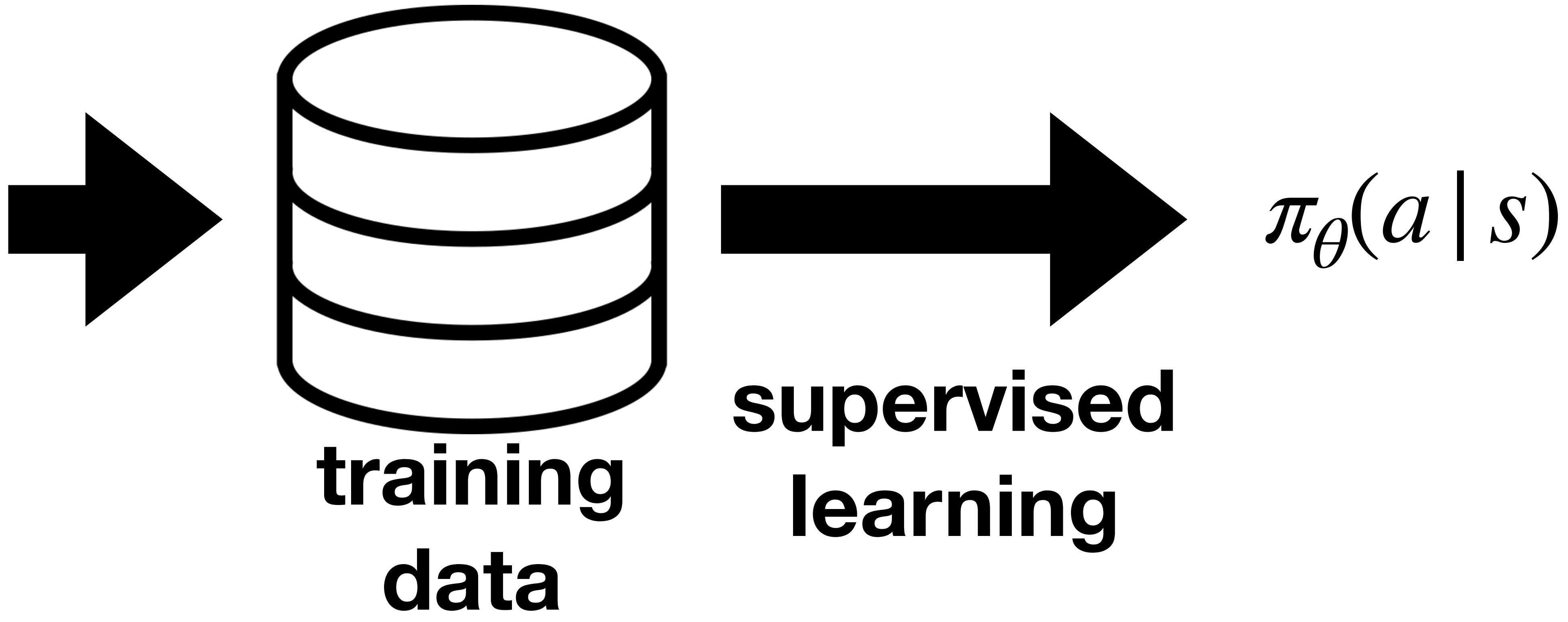
training data

$\mathscr{D} = \{(s_t^{(i)}, a_t^{(i)})\}_{i,t}$

$$\max_\theta \frac{1}{|\mathscr{D}|} \sum_{(s,a)\in\mathscr{D}} \log \pi_\theta(a \,|\, s)$$

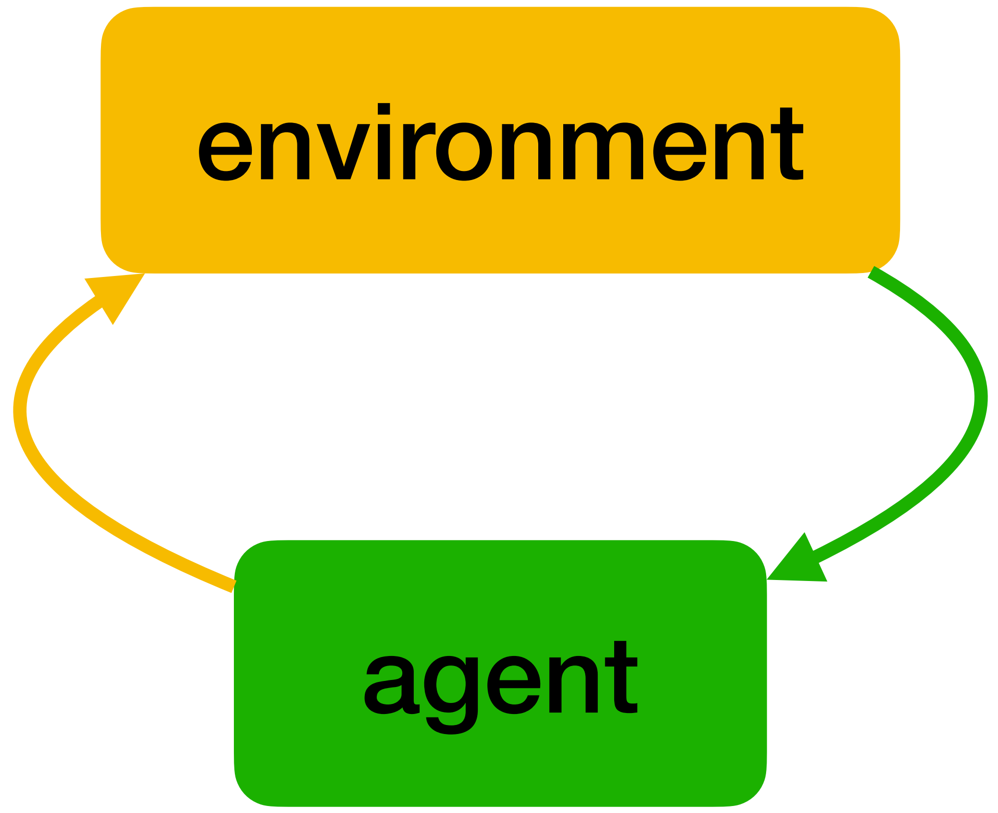
$\pi_\theta(a \,|\, s)$

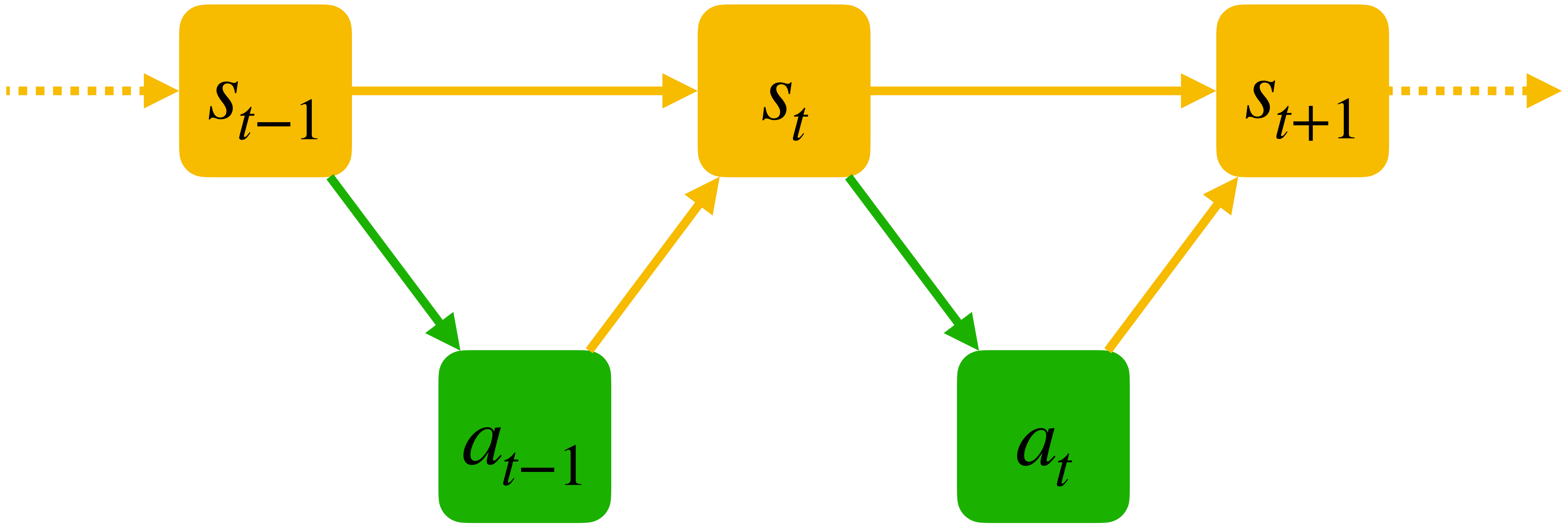
Behavior Cloning (BC)

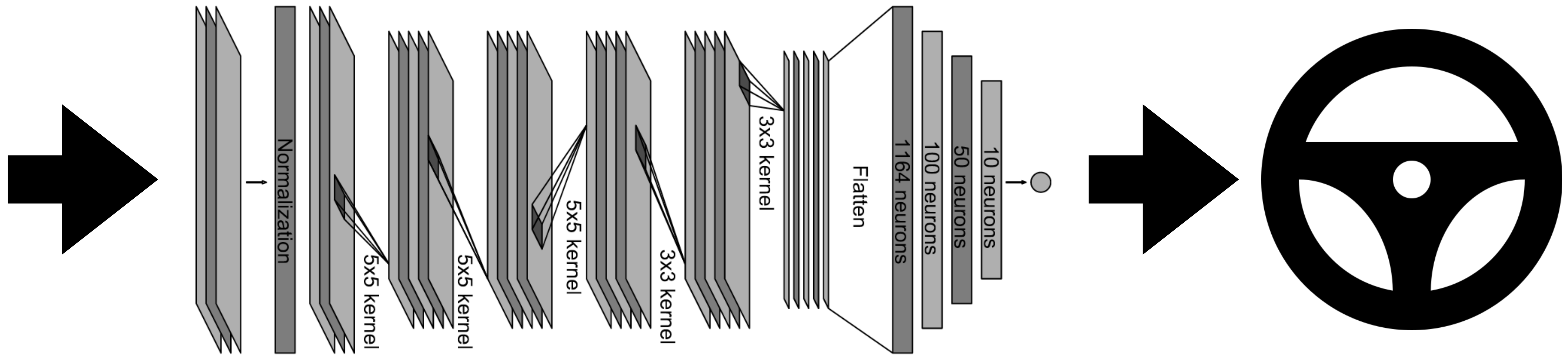


- Benefits:
  - Simple, flexible — can use any learning algorithm
  - Model-free — never need to know the environment
- Drawbacks:
  - Only as good as the demonstrator
  - Only good in demonstrated states — how do we evaluate?
    - Validation loss (on held out data)? Task success rate in rollouts?

A policy is a (stochastic) function





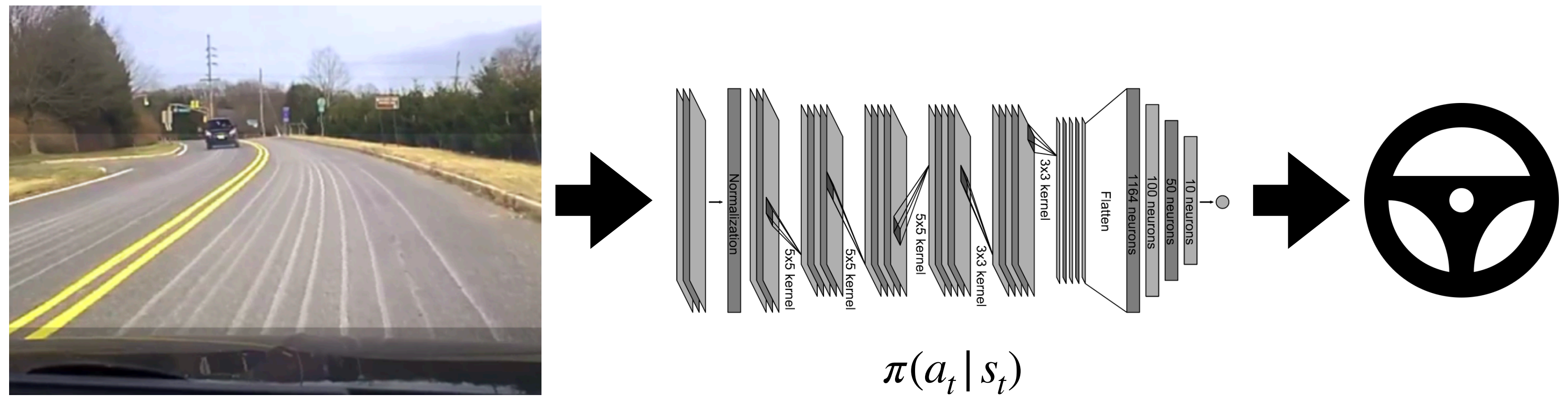


$\pi(a_t \mid s_t)$

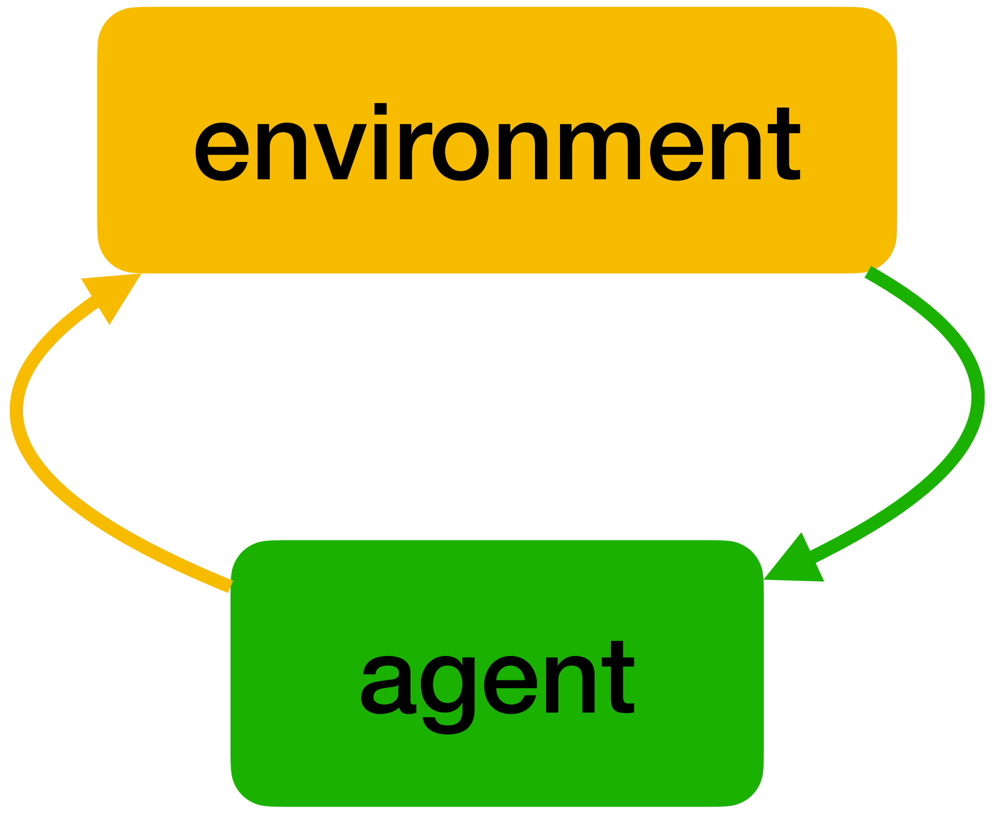
[Bojarski et al., 2016]

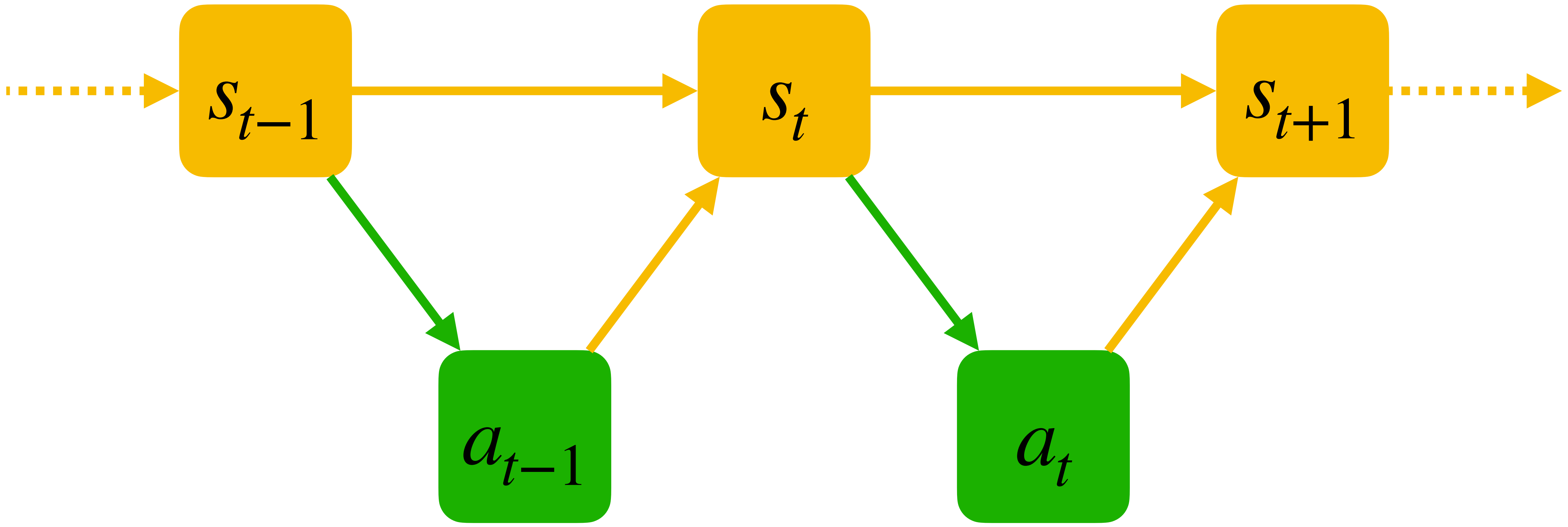
Stochastic policies

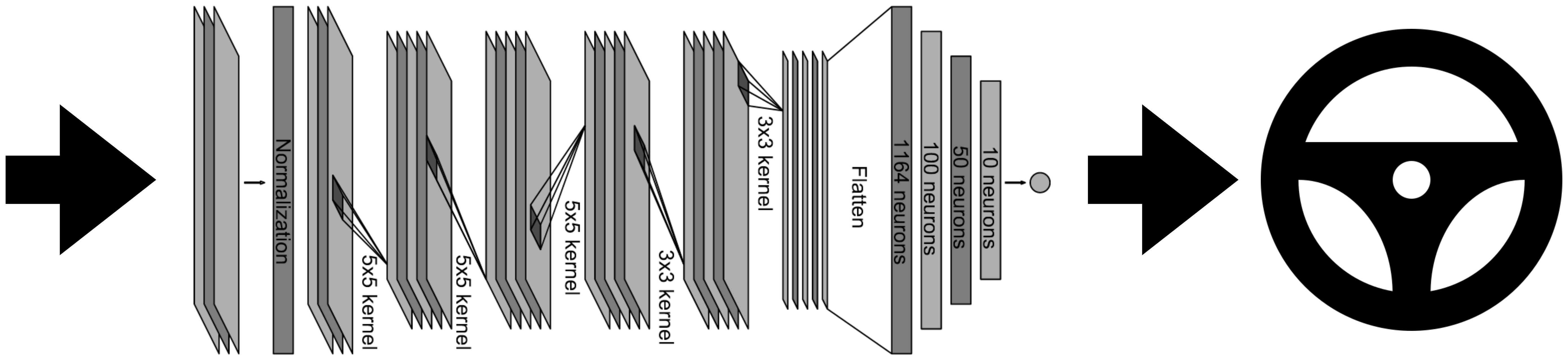
- Learned models are often deterministic functions $f_\theta : x \mapsto y$
- To implement a stochastic policy: output distribution parameters
- Examples:
  - Discrete action space: categorical distribution
    - $\pi_\theta : s \mapsto \{\lambda_a\}_a ; \pi_\theta(a \mid s) = \text{softmax}_a \lambda_a \propto \exp \lambda_a$
  - Continuous action space: Gaussian distribution
    - $\pi_\theta : s \mapsto (\mu, \Sigma) ; \pi_\theta(a \mid s) = \mathcal{N}(\mu, \Sigma)$



A policy is a (stochastic) function

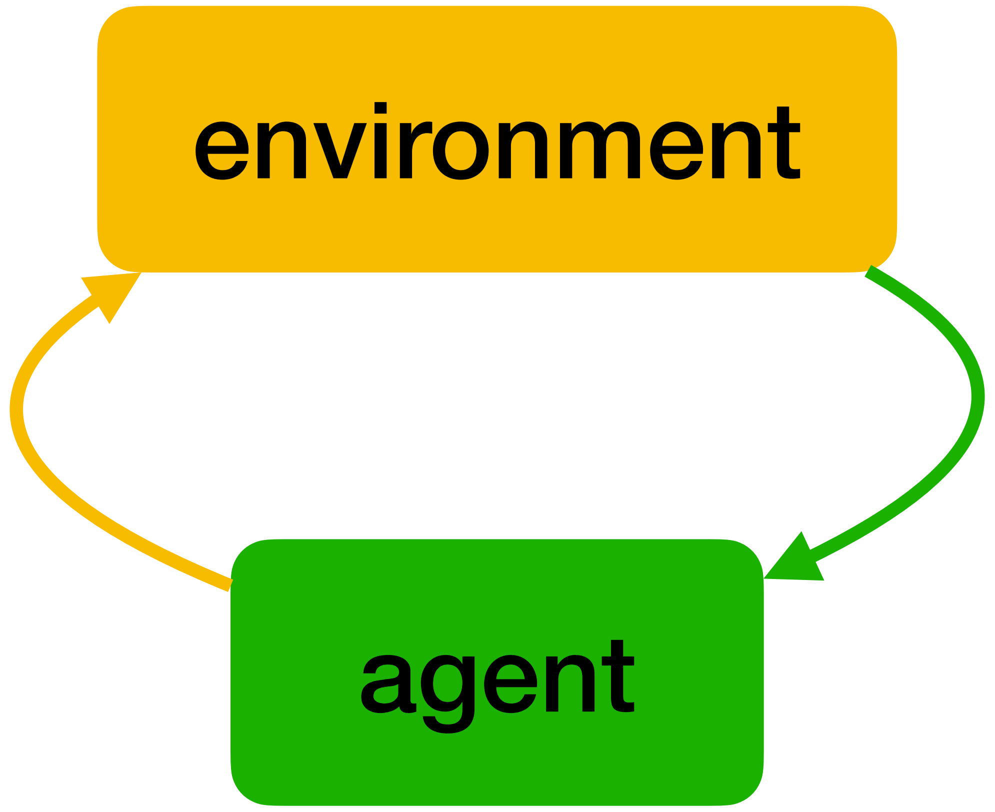


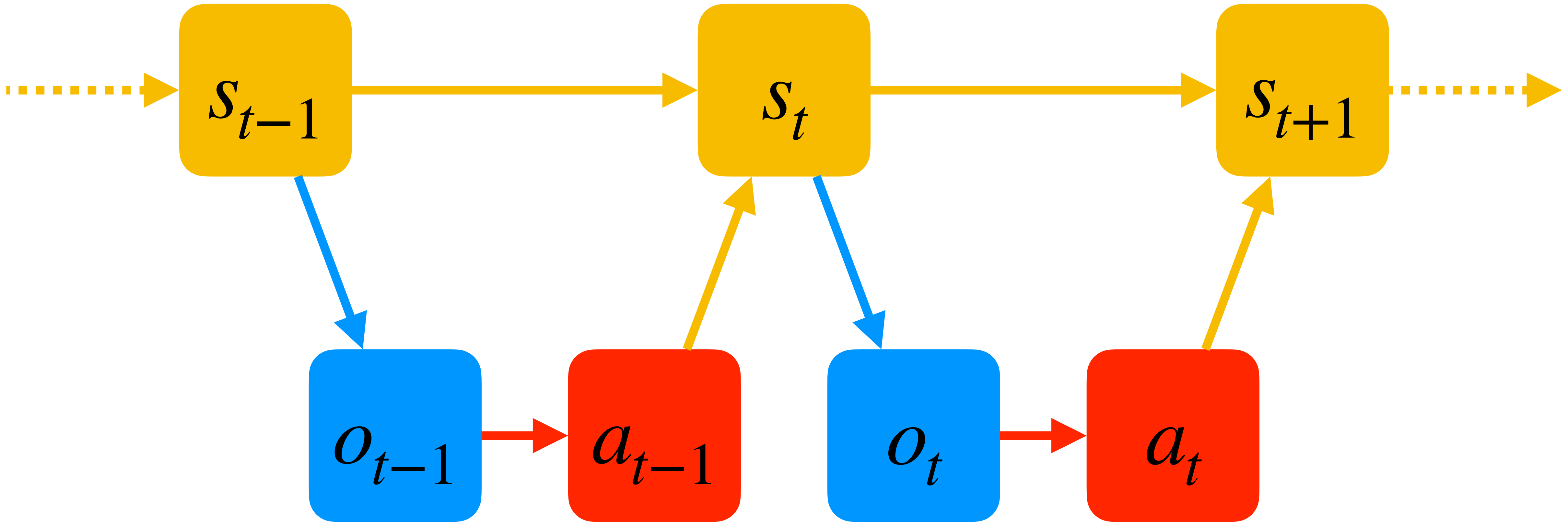


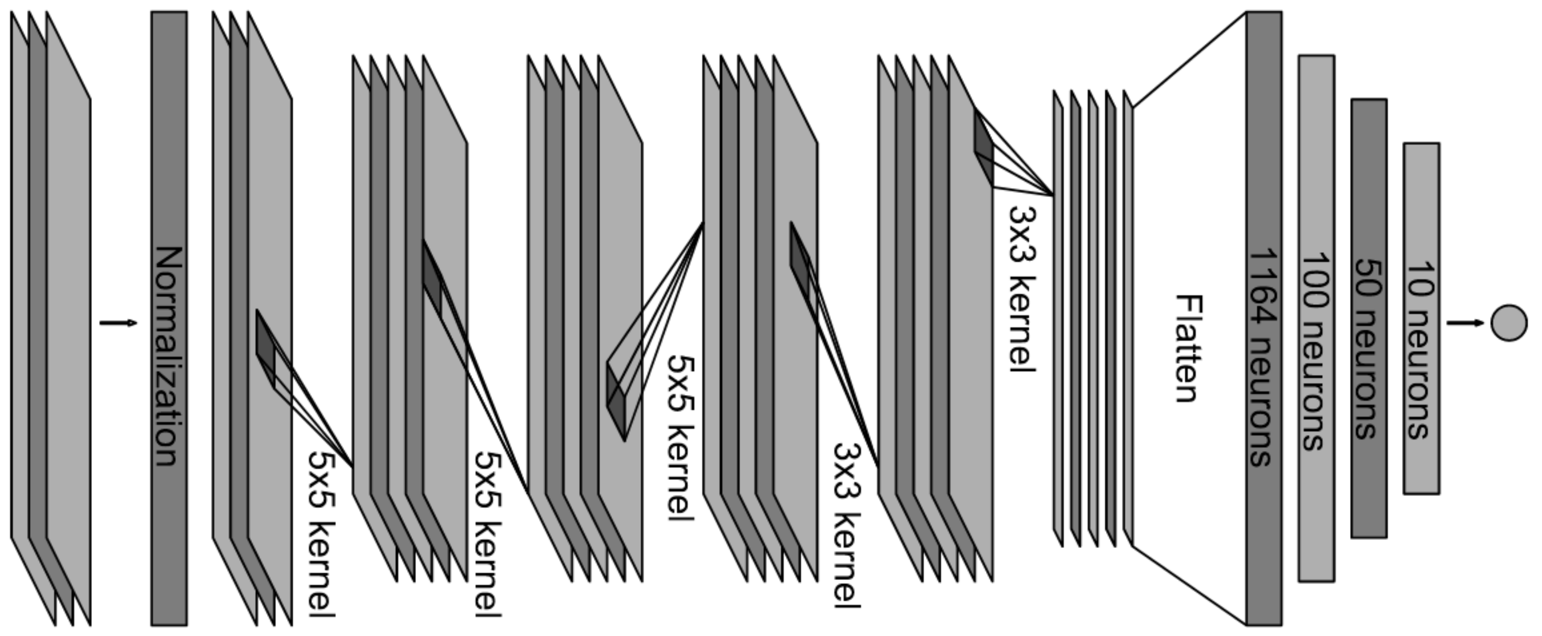


$$\pi(a_t \mid s_t)$$

A policy is a (stochastic) function







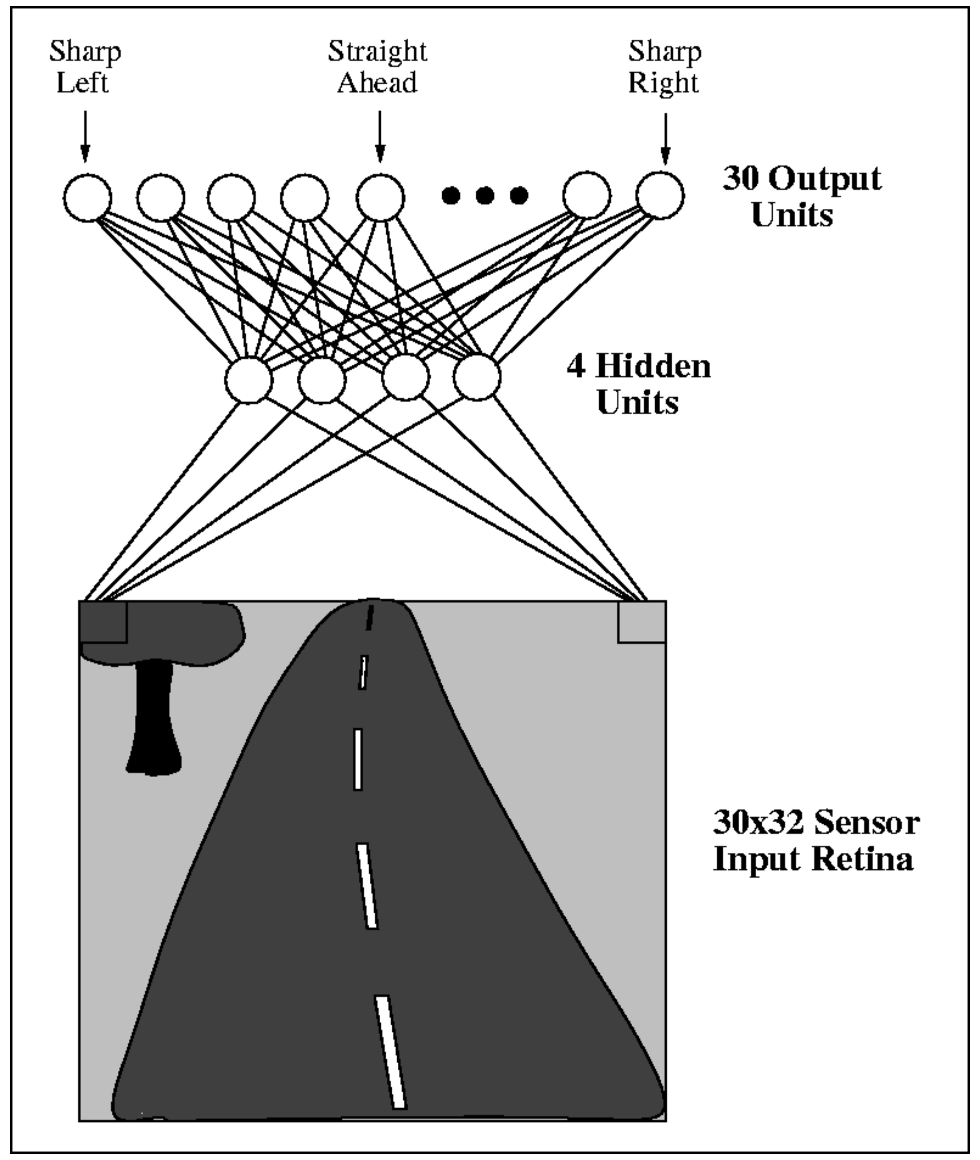
$\pi(a_t | o_t)$

observation

action

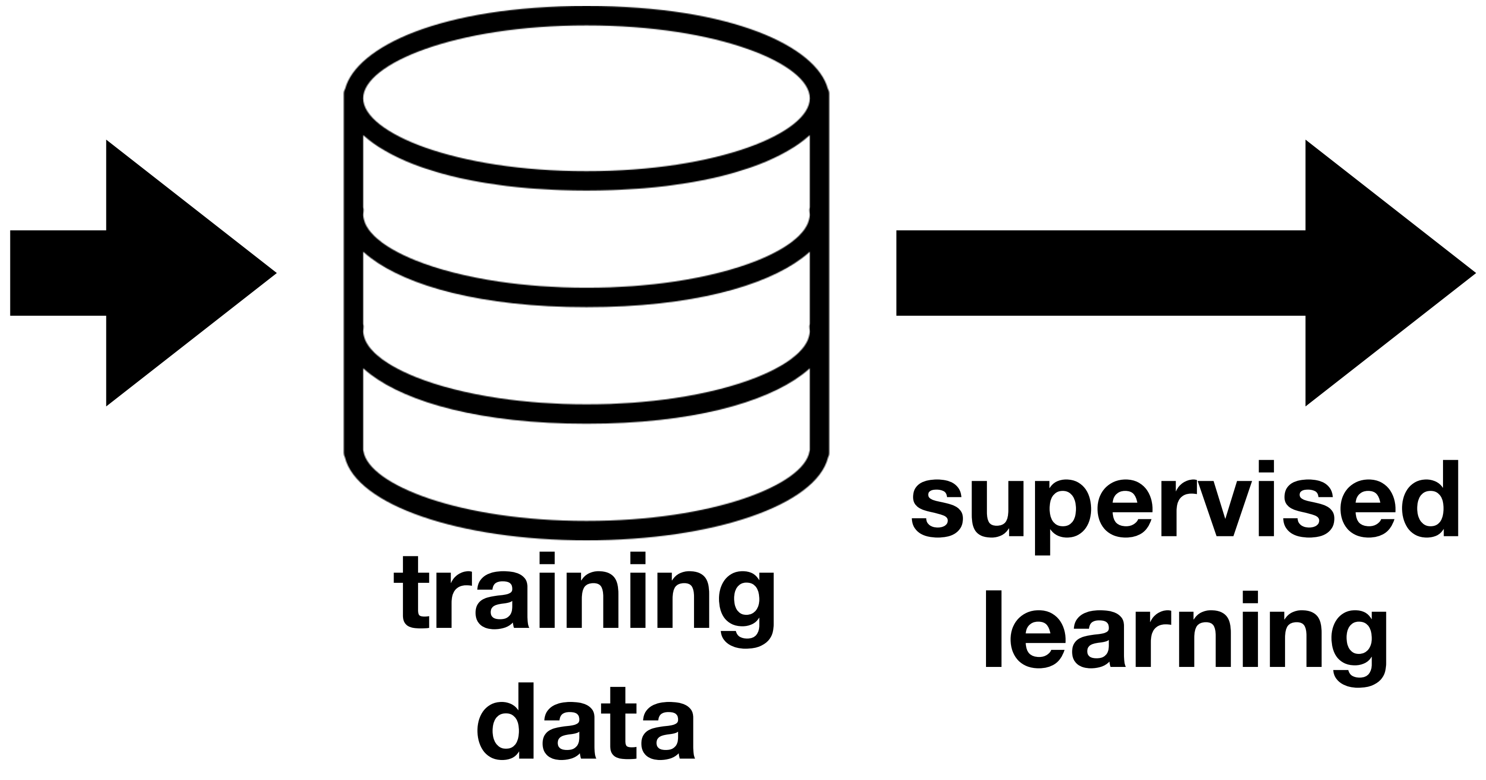
ALVINN

- Autonomous Land Vehicle in a Neural Network (ALVINN, 1989)



[Pomerleau, 1989]

Inaccuracy in BC



$\pi_\theta(a|s)$

- We could evaluate on held out teacher data, but really interested in using π_θ
- If the policy approximates the teacher $\pi_\theta(a_t|s_t) \approx \pi^*(a_t|s_t)$
  - The trajectory distribution will also approximate teacher behavior $p_\theta(\xi) \approx p^*(\xi)$
- But errors accumulate over time
  - May reach states not seen in the training dataset

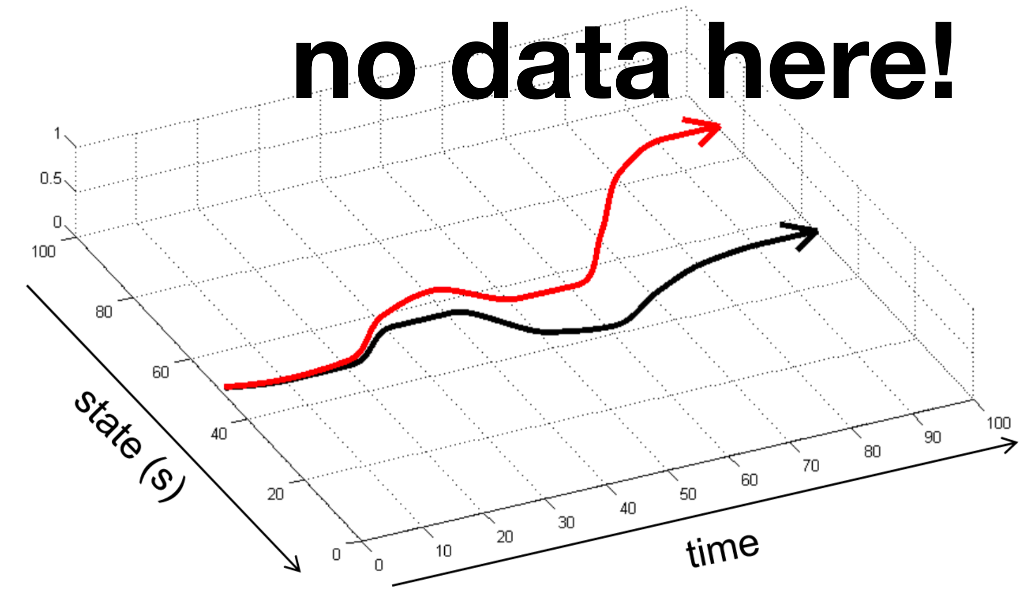
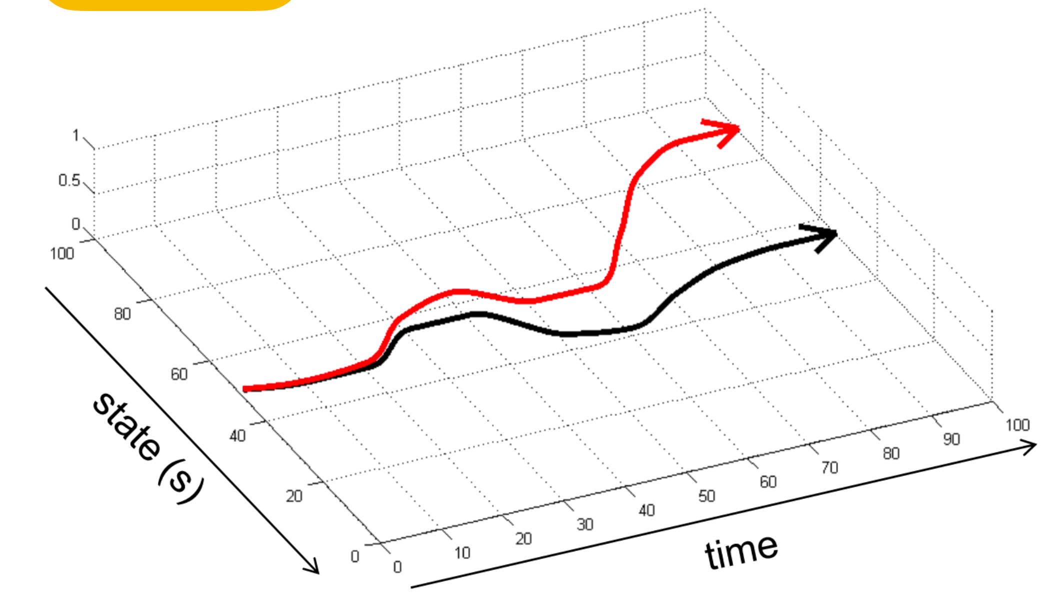


Image: Sergey Levine

The impact of inaccurate dynamics

$$\dashrightarrow s_{t-1} \rightarrow s_t \rightarrow s_{t+1} \dashrightarrow$$



- Errors in learning are unavoidable
- What impact do they have on sequential behavior?
- Bounded one-step error in a dynamical model $\sum_{s'} \left| p_\theta(s' \,|\, s) - p^*(s' \,|\, s) \right| \leq \epsilon$
  - Can lead to growing error over time $\sum_{s_t} \left| p_\theta(s_t) - p^*(s_t) \right| \leq \epsilon t$
  - Not too bad by itself, but can drift outside training distribution $\mathscr{D}$

Today's lecture

Behavior Cloning

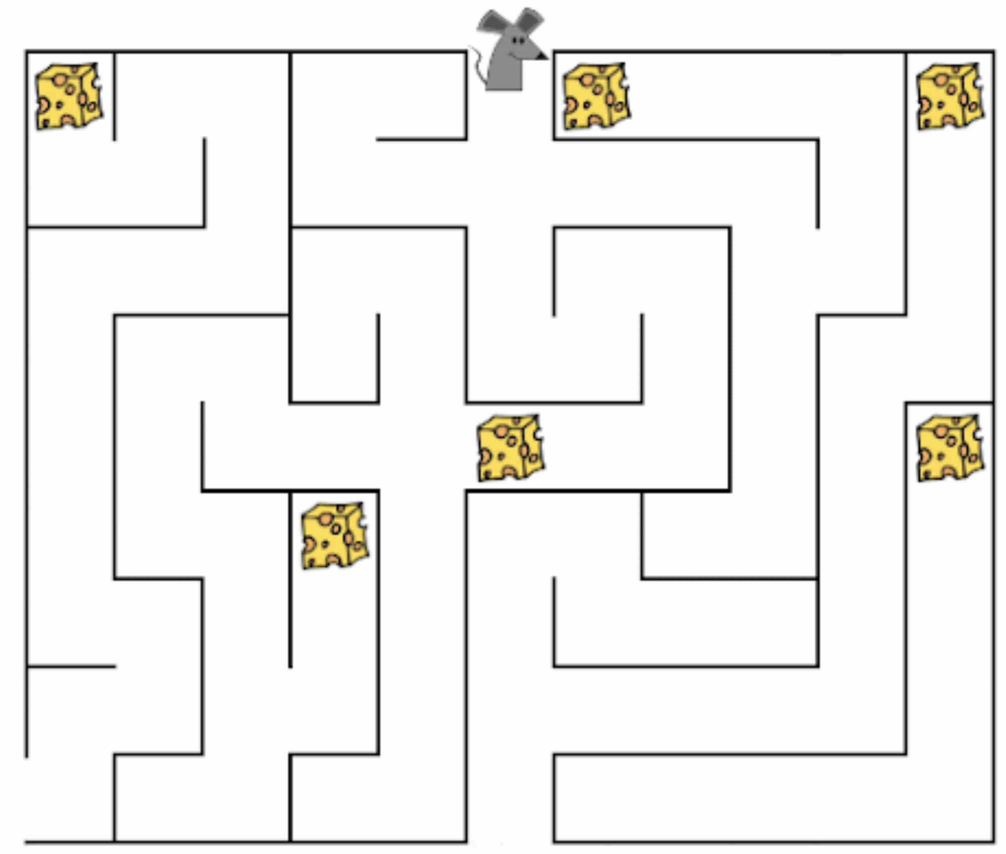
Better behavior modeling

Alleviating train–test mismatch

Modeling other agents is hard

- Is there sufficient data? Demonstrating puts a burden on the teacher
- Are demonstrations correct? Humans are fallible, some supervision is hard
- Are demonstrations consistent? Some tasks can be done in multiple ways
- Is the state partially observable? $o_t \stackrel{?}{=} s_t$
- Are the learner and teacher observations the same? $o_t \stackrel{?}{=} o_t^*$

Inconsistent demonstrations: multiple goals



- What if the task is to reach one of multiple goals?
  - Different episodes can successfully reach different goals
  - We need to train one policy to reach multiple goals
- If we know the goal, condition on it
  - Goal-conditioned policy: $\pi_\theta(a_t | s_t, g)$
- More generally: task-conditioned policy $\pi_\theta(a_t | s_t, \tau)$
  - Goal = desired final state; but how to represent other kinds of tasks?

Image: puzzlesandriddles.com

Goal-conditioned Behavior Cloning

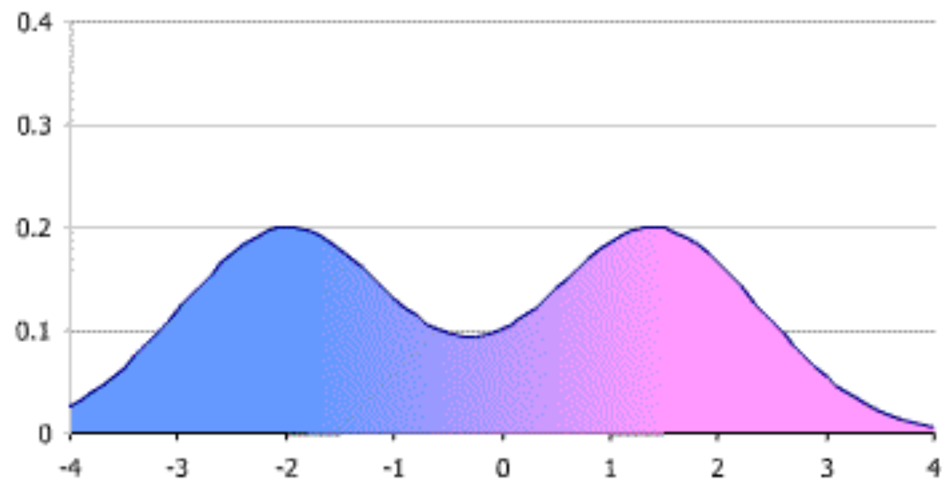
- Can we train a goal-conditioned policy $\pi_\theta(a_t \mid s_t, g)$ from demonstrations?
  - Assume goal = state that the agent should reach
- How can we know the goal in demonstrations $\xi = s_0, a_0, s_1, a_1, \ldots$?
  - Manual labeling? $\mathscr{D} = \{(\xi^{(i)}, g^{(i)})\}_i$
- Hindsight: take each s_t as the goal of the trajectory leading to it

$$s_0, a_0, \ldots, s_{t-1}, a_{t-1}, s_t = g$$

  - Supervised learning of $\pi(a \mid s, g)$ from data points $((s_t, g = s_{t'}), a_t)$ for $t' > t$

Inconsistency due to multimodal behavior

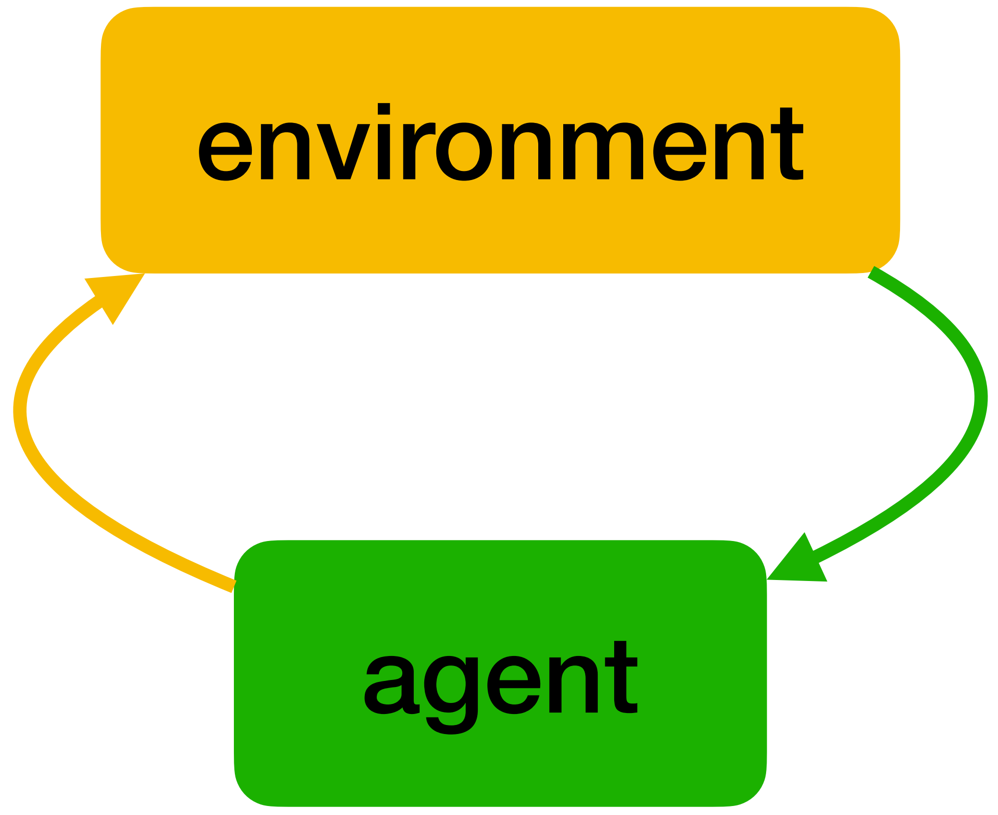
- Goal-conditioning assumes known goals
  - More generally, known behavior modifiers
- Usually, the behavior mode is unknown
  - Need multimodal policy $\pi(a \mid s)$
    - Mixture models (e.g. GMM)
    - Latent-variable models (e.g. normalizing flows)
  - Need to be consistent along a trajectory
    - Condition the policy on memory of past actions $\pi(a_t \mid s_t, a_{\leq t})$

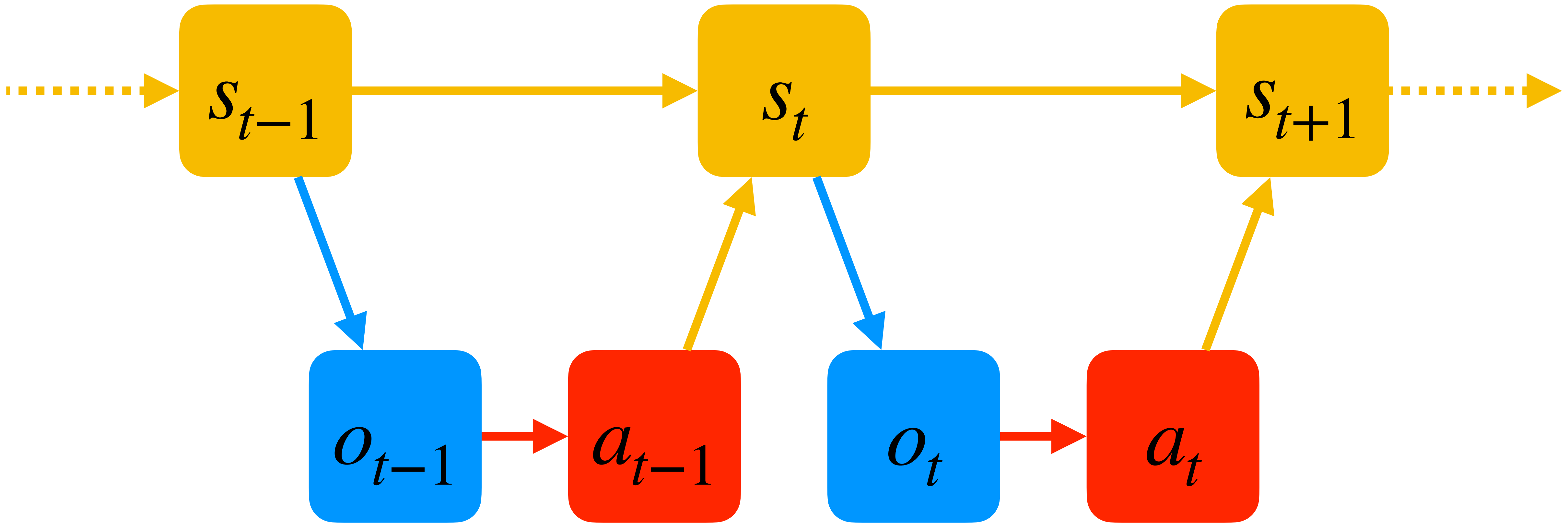


Modeling partially observable behavior

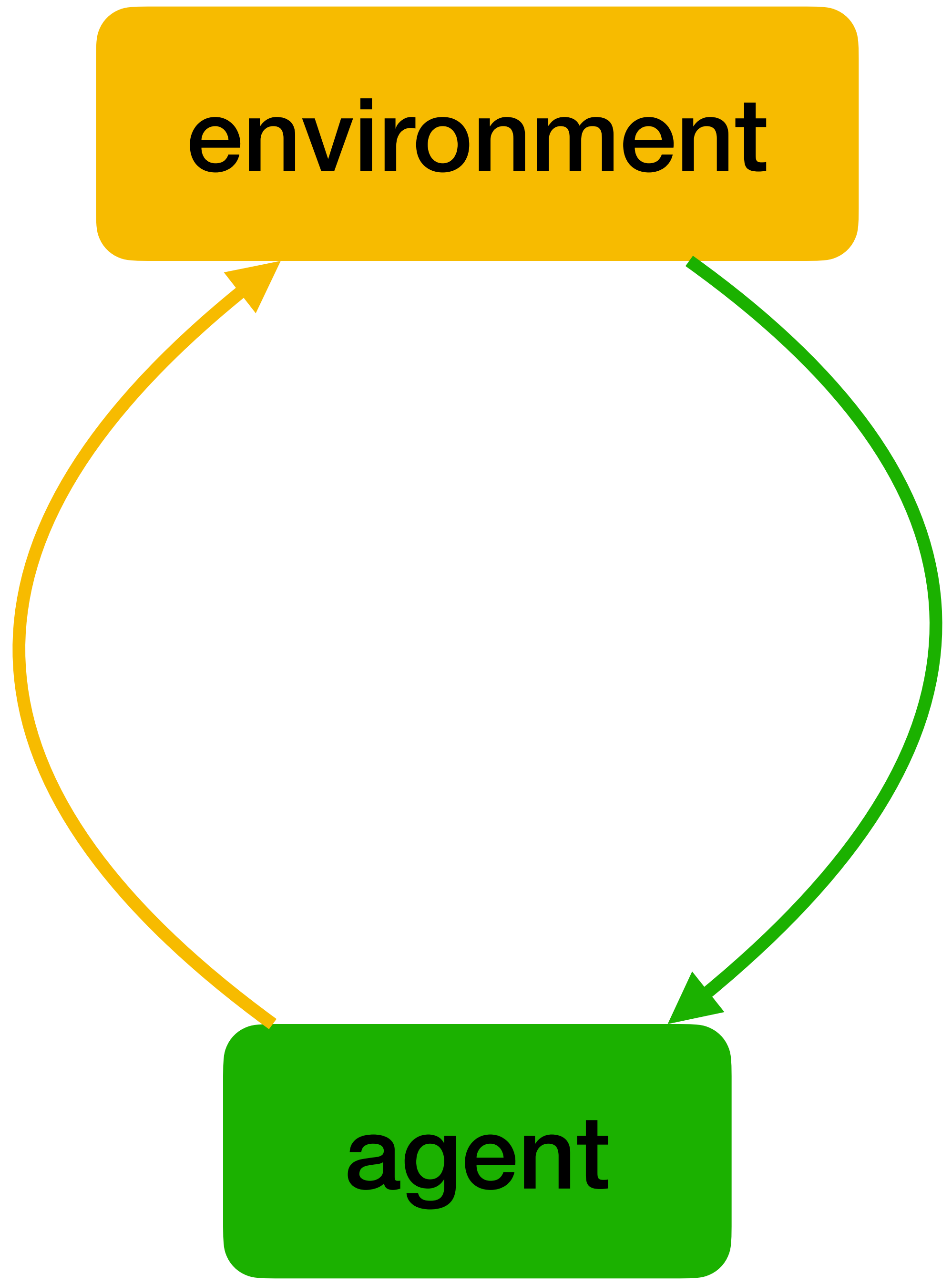
- Partial observations are not Markov
  - Generally, this means $p(o_{t+1} \mid o_t, a_t) \neq p(o_{t+1} \mid o_{\leq t}, a_{\leq t})$
  - Reactive policy $\pi_\theta(a_t \mid o_t)$ may not be optimal
    - May need $\pi_\theta(a_t \mid o_{\leq t})$, or even $\pi_\theta(a_t \mid o_{\leq t}, a_{<t})$; but how?
- Can use RNNs $f_\theta : (h_{t-1}, a_{t-1}, o_t) \mapsto h_t$, or other memory models
- But memory state is latent in demonstrations
  - Modeling memory is hard → prior structure may help; more on this later

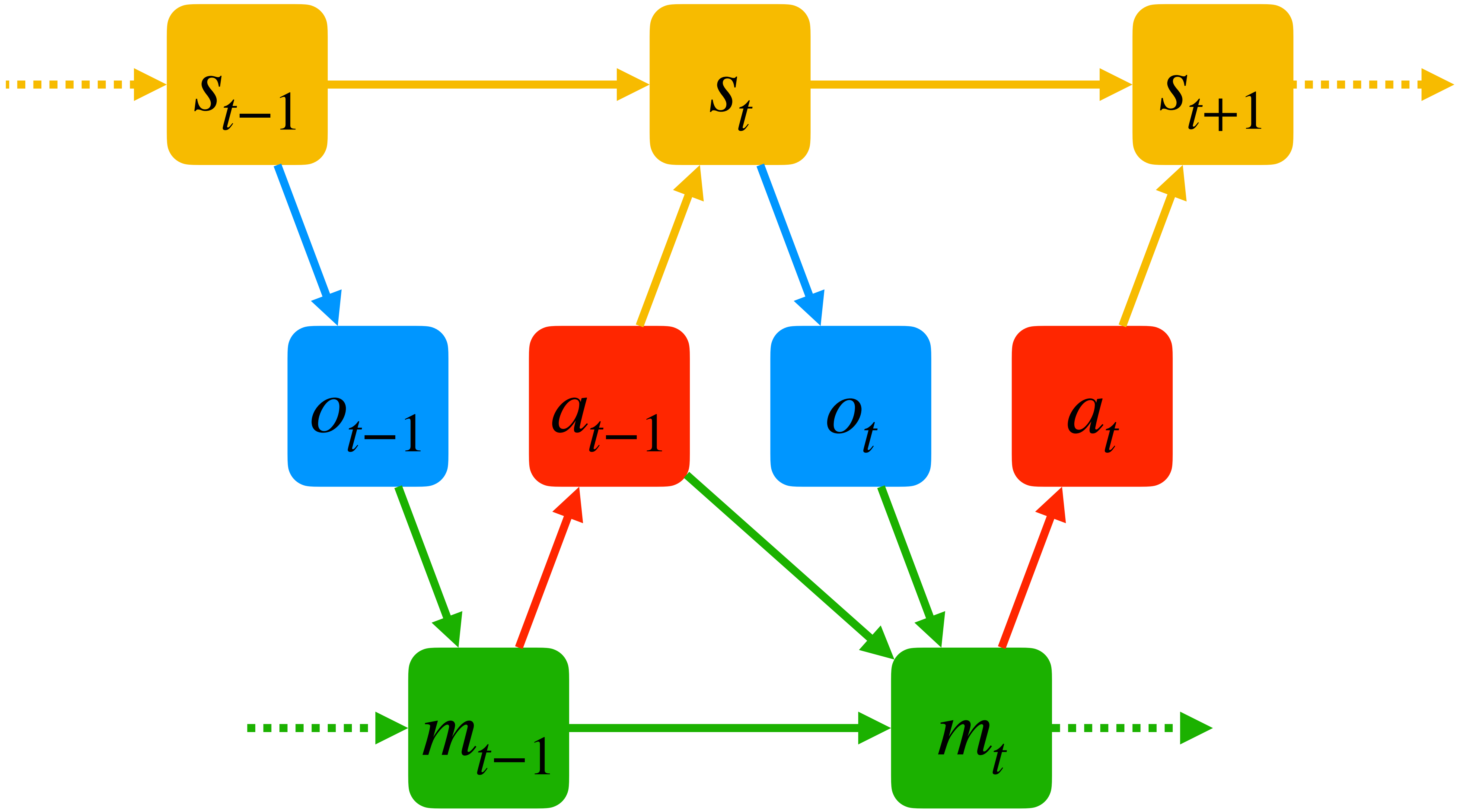
Modeling memory





Modeling memory





$$\pi_\theta(m_t, a_t \mid m_{t-1}, a_{t-1}, o_t)$$

- A common architecture:
  - A recurrent model $m_t = f_\theta(m_{t-1}, a_{t-1}, o_t)$; and an action model $\pi_\theta(a_t \mid m_t)$

Today's lecture

Behavior Cloning

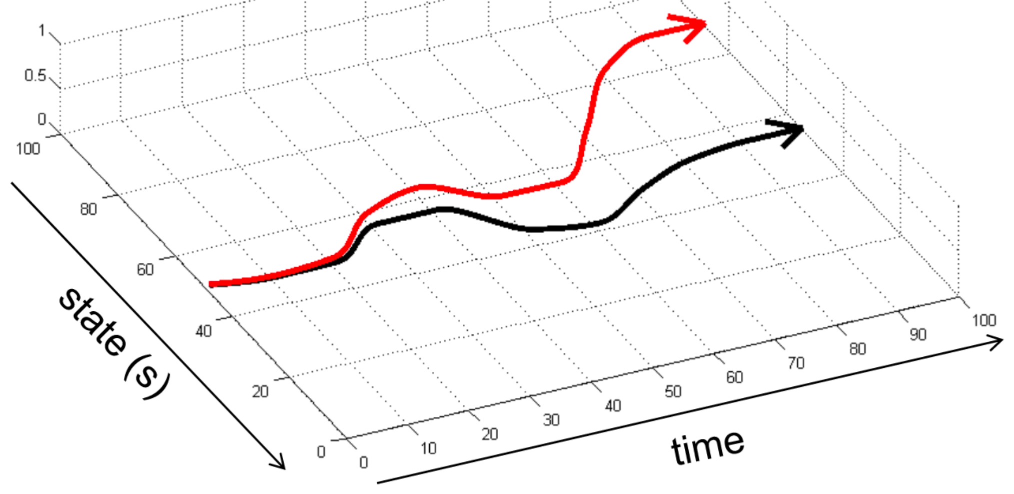
Better behavior modeling

Alleviating train–test mismatch

Alleviating train–test mismatch

- ML promises generalization when training distribution = test distribution
  - But this is challenging in IL: errors accumulate
  - We can quickly get to error states that we haven't seen fixed
  - Train–test distribution mismatch = covariate shift

no data here!

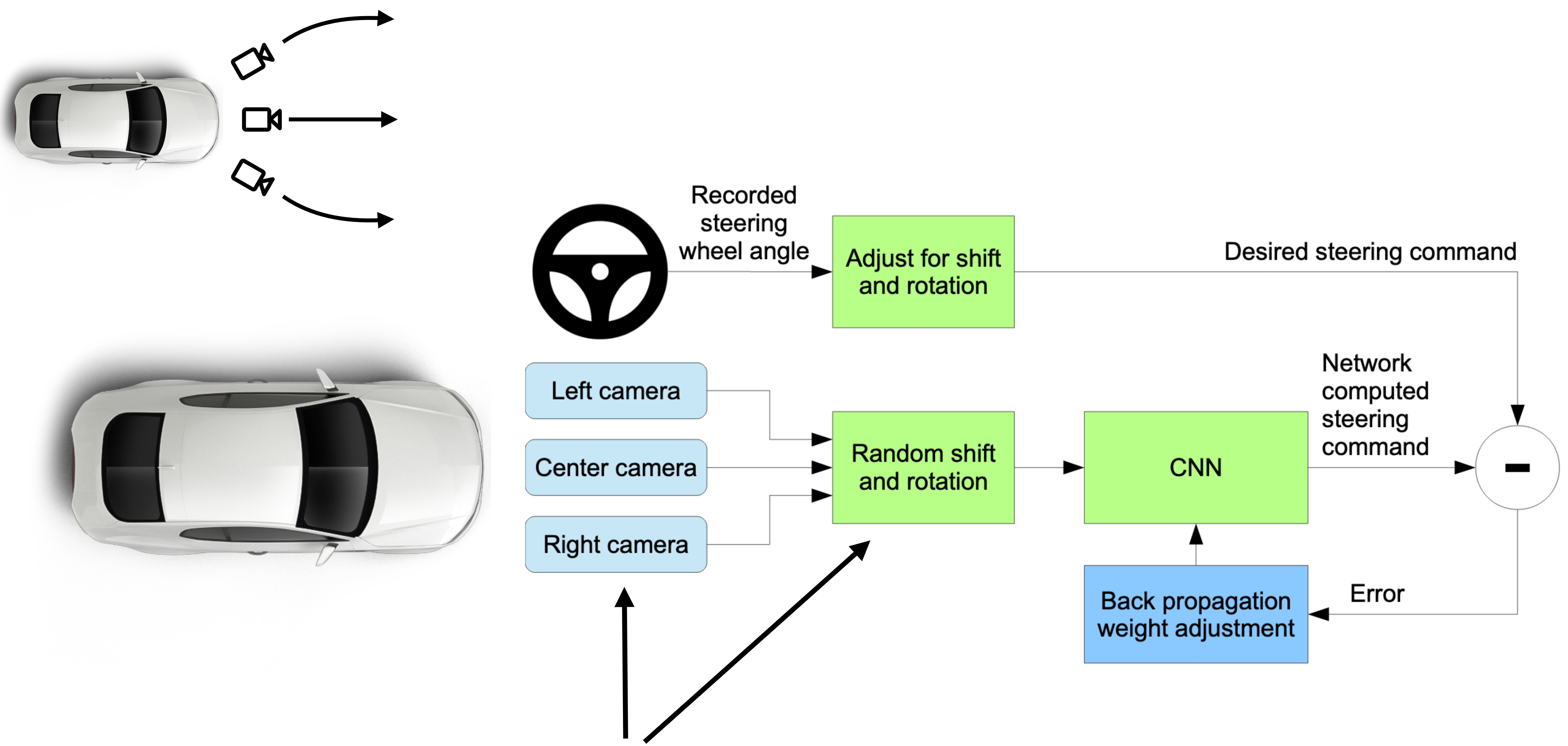


- Ideas:
  - Augment the training dataset to expand the distribution
  - Update train distribution → test distribution
  - Intervene during demonstrations to expand the distribution

Imitation Learning can work

Video: NVIDIA

How did they do it?



augmented data to better cover test distribution

[Bojarski et al., 2016]

DAgger: Dataset Aggregation

- Can we collect demonstration data from the test distribution?
  - We don't know $p_\theta(\xi)$ until we're done training θ
  - But we get closer and closer during training

Algorithm DAgger

Collect dataset $\mathcal{D}$ of teacher demonstrations $\xi \sim p^*$

repeat

  Train π_θ on $\mathcal{D}$

  Execute π_θ to get $\xi \sim p_\theta$

  $\boxed{\text{Ask teacher to label } (a_t^* | s_t) \sim \pi^*}$

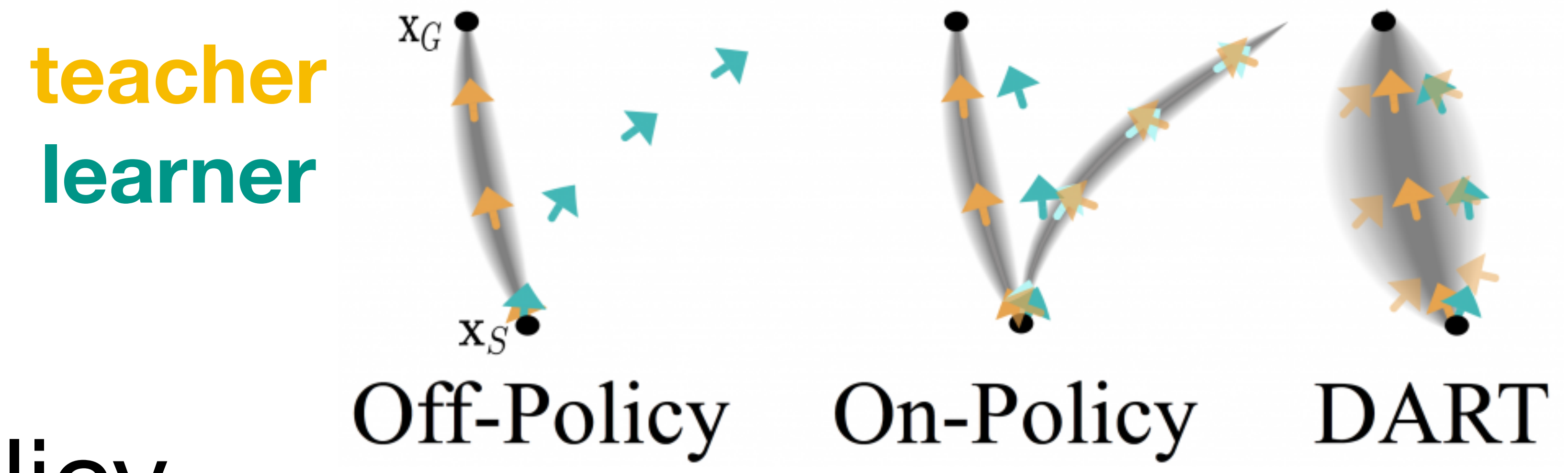
  Aggregate $\{(s_t, a_t^*)\}_t$ into $\mathcal{D}$

but how? challenging...

DAgger demo

Video: Stéphane Ross

DART: Disturbances Augmenting Robot Training

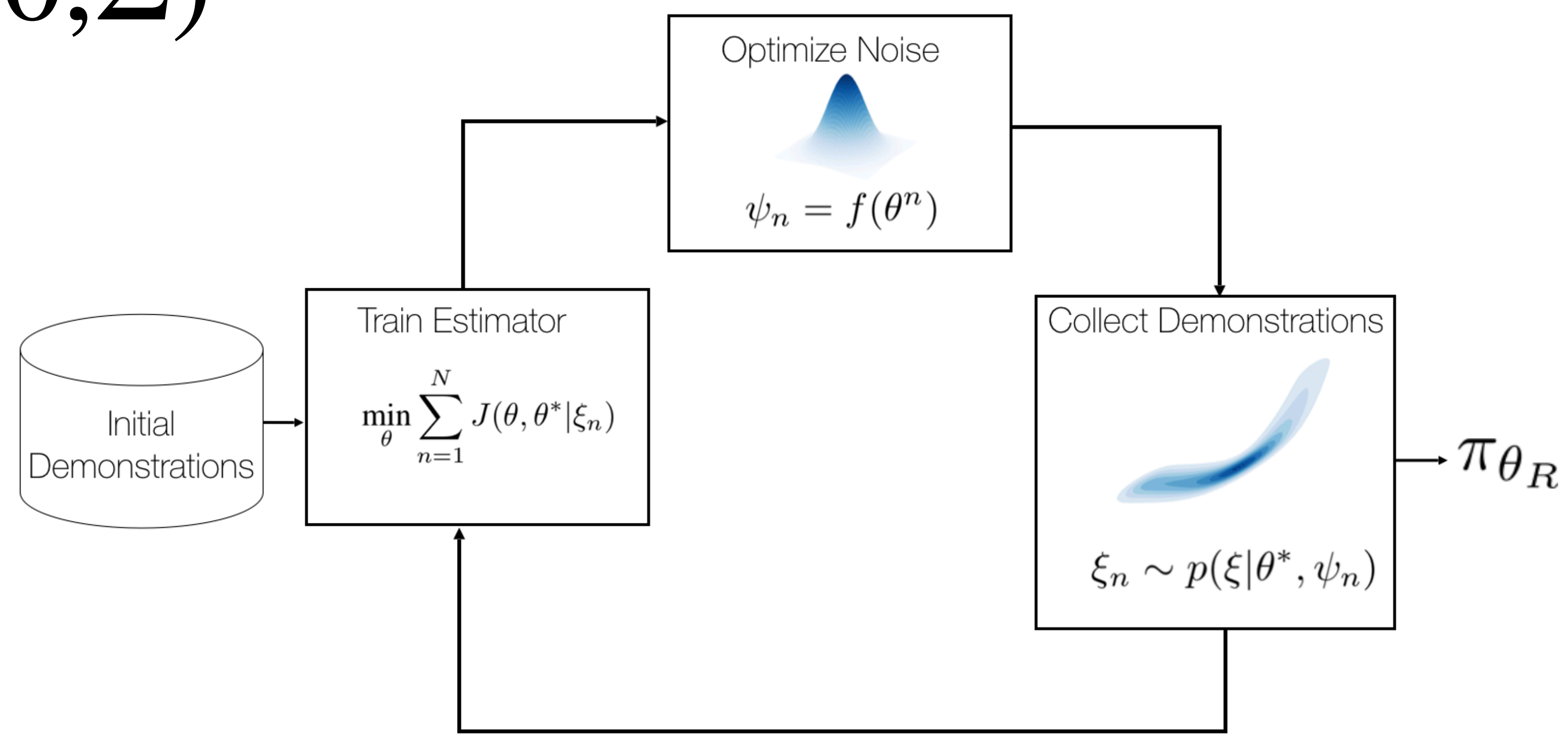


- Off-policy vs. on-policy
  - On-policy = data comes from the learner's current policy
  - Off-policy = data comes from another policy (another agent or past learner)
- In off-policy IL (e.g. BC) learner may go off the teacher's support
- In on-policy IL (e.g. DAgger) learner initially goes off, until corrected
- DART: increase the data support by injecting noise during demonstrations
  - Force teacher into slight-error states, to see how they are fixed

[Laskey et al., 2017]

DART

- Noise = perturbation of actions $q(\tilde{a} \mid a)$
  - New effective dynamics: $\tilde{p}(s' \mid s, a) = \sum_{\tilde{a}} q(\tilde{a} \mid a) p(s' \mid s, \tilde{a})$
  - For example, in continuous actions: $\tilde{a} = a + \epsilon; \quad \epsilon \sim \mathcal{N}(0, \Sigma)$



Algorithm DART

repeat

Collect dataset $\mathcal{D}$ of teacher demonstrations $\xi \sim \tilde{p}^*$

Train π_θ on $\mathcal{D}$

Update noise q such that p_θ is better supported by $\tilde{p}^*$

Image: Michael Laskey

Grasping task

Behavior Cloning

DART

[Laskey et al., 2017]

Recap

- Imitation Learning = Learning from Demonstrations
  - Learn policy $\pi(a \mid s)$ from teacher demonstrations
- Behavior Cloning: supervised learning
  - Minimize loss, e.g. NLL, on training set of trajectories
- Accurate imitation is crucial
  - Improve imitation through goal-conditioning, multimodal policies, memory, etc.
- Errors accumulate and cause train–test distribution mismatch
  - Can be alleviated through augmentation, on-policy data collection, noise injection