

Generalization in Large scale MDPs

Sham Kakade and Wen Sun

CS 6789: Foundations of Reinforcement Learning

Recap on Bellman Error and Bellman Operator

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If $BE(s, a) \neq 0$, then $f \neq Q^*$

Notations

Probability of π visiting (s, a) at time step h : $d_h^\pi(s, a)$

Question for Today

We have seen tabular MDP and linear MDP, is there a **more general framework** that captures these two, and potentially many more, where efficient learning is possible?

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In other words, what structural conditions permit RL generalization, provably?

Outline for Today

1. Bellman rank Definitions

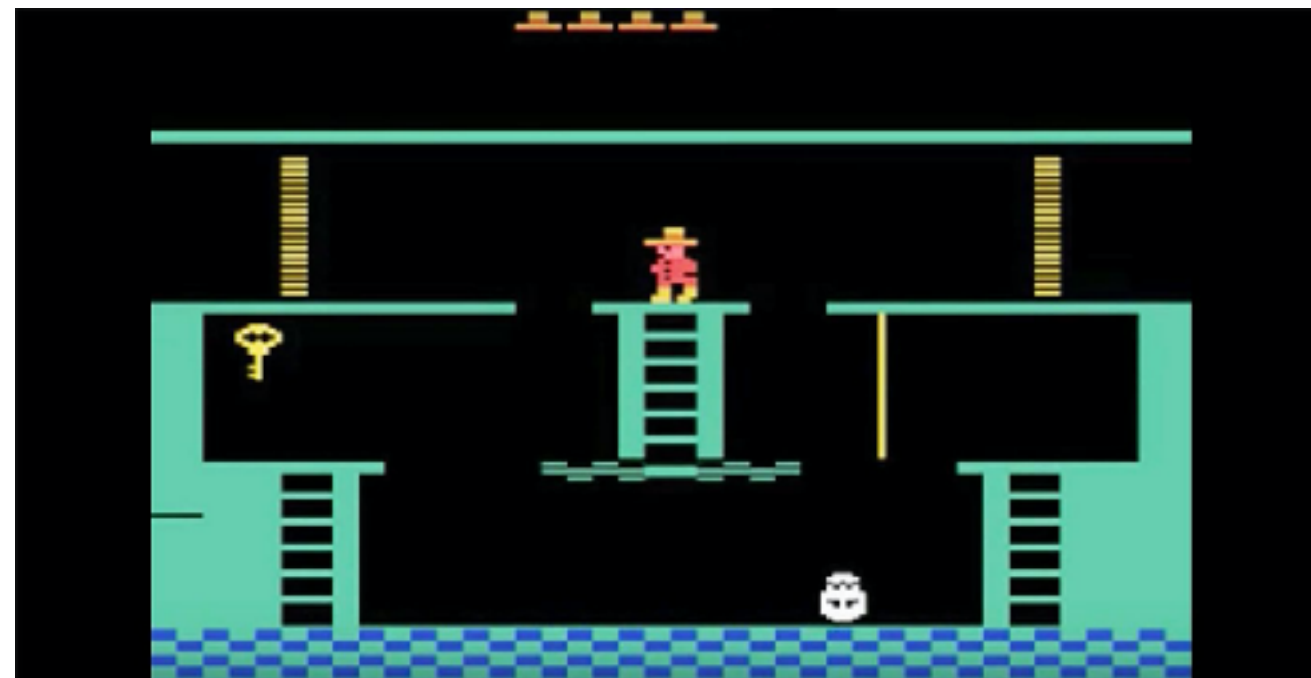
2. Examples that are captured by the Bellman rank framework

Setting

Finite horizon episodic MDP $\{ \{S_h\}_{h=0}^H, \{A_h\}_{h=0}^{H-1}, H, s_0, r, P \}$

State space S_h is extremely large:

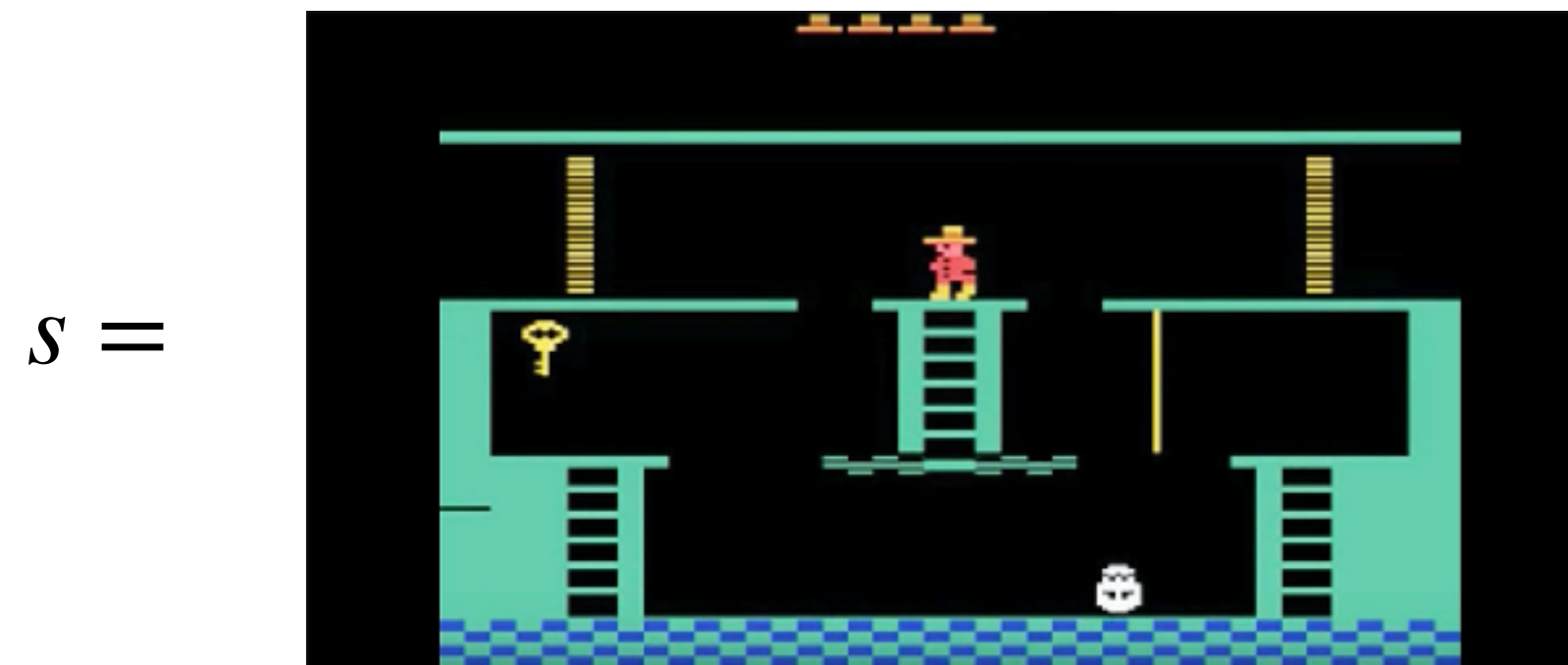
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Not acceptable: $\text{poly}(|S|)$

Need to generalize via (nonlinear) function approximation

Let's set up function class in RL setting

We will consider **Q function class**

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Define **value function class**: $\mathcal{V} = \{ V_f : V_f(s) = \arg \max_a f(s, a) \mid f \in \mathcal{F} \}$

Learning Goal:

We will do PAC in this lecture rather than regret.

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Given approximation error ϵ and failure prob δ ,
can we learn ϵ *near optimal policy* (i.e., $V^{\hat{\pi}} \geq V^* - \epsilon$) in # of samples scaling
poly with all relevant parameters (*here, we need poly in $\ln(|\mathcal{F}|)$*)

How to check if a Q-approximator is good?

We define **average** Bellman error of a Q-estimate g below:

$$\mathcal{E}(g; f, h) = \mathbb{E}_{s_h, a_h \sim d_h^{\pi_f}} \left[g(s_h, a_h) - r(s_h, a_h) - \mathbb{E}_{s_{h+1} \sim P(\cdot | s_h, a_h)} \left[\max_{a \in \mathcal{A}} g(s_{h+1}, a) \right] \right]$$

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The Q / V-Bellman rank

$$\forall h : \mathcal{E}_h \in \mathbb{R}^{|\mathcal{F}| \times |\mathcal{F}|}$$

	g	f			
π_f	$\mathcal{E}_{g;f,h}$	$\mathcal{E}_{f;f,h}$			

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Rank of this Matrix is defined as Bellman Rank

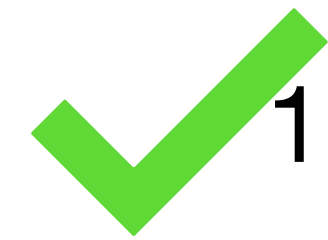
The Q / V-Bellman rank

In other words, there are two mappings $W_h : \mathcal{F} \mapsto \mathbb{R}^d$, $X_h : \mathcal{F} \mapsto \mathbb{R}^d$ (d = Bellman-rank)

$$\forall f, g \in \mathcal{F} : \mathcal{E}(g; f, h) = \langle W_h(g), X_h(f) \rangle$$

Note, we just assume the existence of W, X , but they are unknown

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2. Examples that are captured by the Bellman rank framework

The Linear Bellman Completion Model

Given feature ϕ , take any linear function $\theta^\top \phi(s, a)$:

$$\forall h, \exists w \in \mathbb{R}^d, s.t., w^\top \phi(s, a) = r(s, a) + \mathbb{E}_{s' \sim P_h(s, a)} \max_{a'} \theta^\top \phi(s', a'), \forall s, a$$

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Note linear Bell-completion captures tabular / linear mdp already

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As we will see, linear Q^* & V^* is learnable, and recall linear Q^* is not...

Q^* - state abstraction

We have a small latent state space Z , and a **known** mapping ξ from state s to z

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Claim: this model has Q-Bellman rank $|Z| |A| + |Z|$

We can show that this model is captured by linear Q^* & V^*

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Low-rank MDP

$$P_h(s' | s, a) = \mu_h^\star(s')^\top \phi_h^\star(s, a) \quad (\text{neither } \mu^\star \text{ nor } \phi^\star \text{ is known})$$

Claim: this model has V-Bellman rank d

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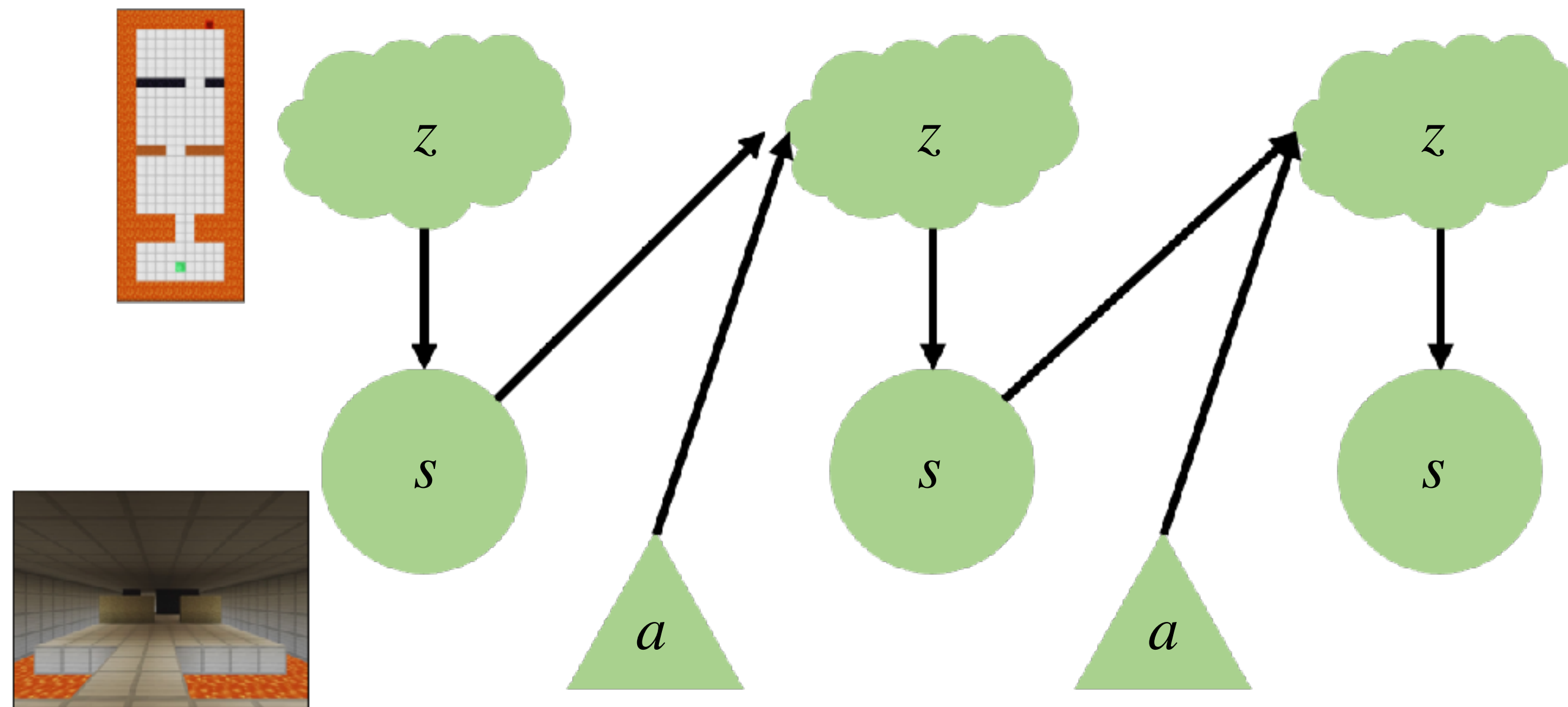
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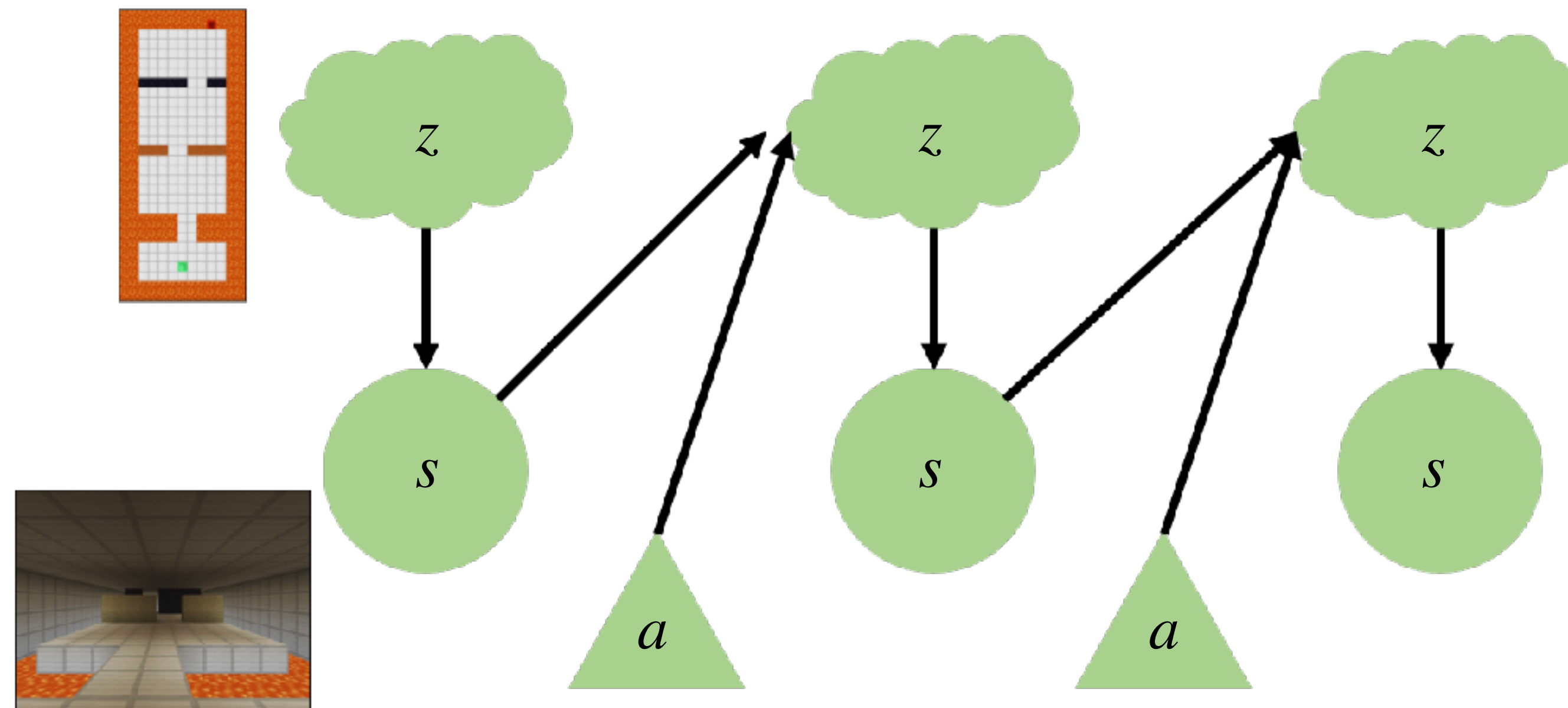
Latent variable MDP

Latent variable MDP is captured by low-rank MDP, so it has small V-Bellman rank...



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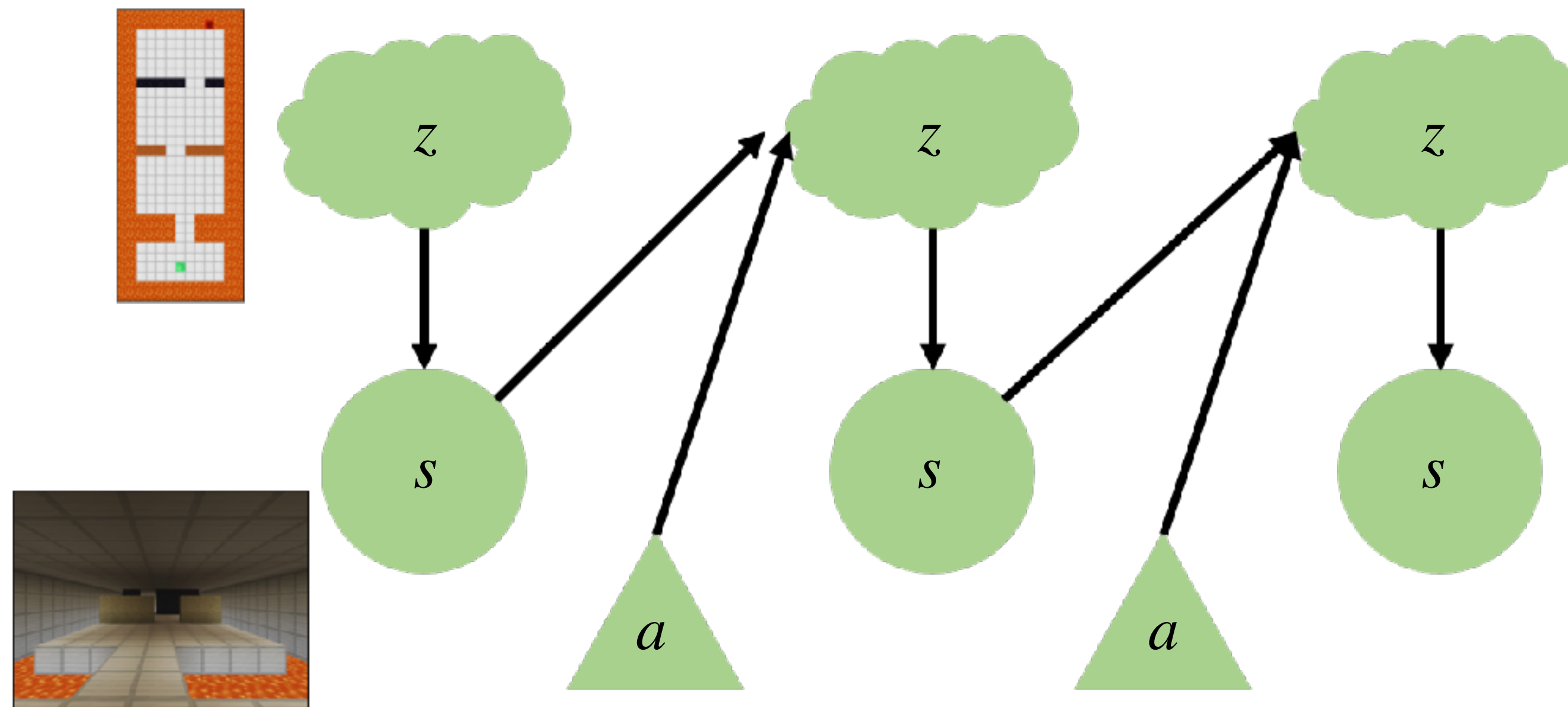
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Given $s, a: z \sim \phi^*(s, a), s' \sim \nu^*(z)$

V-Bellman rank = Number of latent states

Summary

1. Q-Bellman rank: related to the Bellman error of a Q function estimate g :

$$\mathcal{E}(g; f, h) = \mathbb{E}_{s_h, a_h \sim d_h^{\pi_f}} \left[g(s_h, a_h) - r(s_h, a_h) - \mathbb{E}_{s_{h+1} \sim P(\cdot | s_h, a_h)} \left[\max_{a \in \mathcal{A}} g(s_{h+1}, a) \right] \right]$$

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4. Many models (more in the book chapter) indeed have low-Q or V Bellman rank

Next week:

A general algorithm that can learn an ϵ near optimal policy w/ # of samples

$\text{poly}(H, 1/\epsilon, \ln(|\mathcal{H}|), \text{b-rank})$