

# 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  $\pi$  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

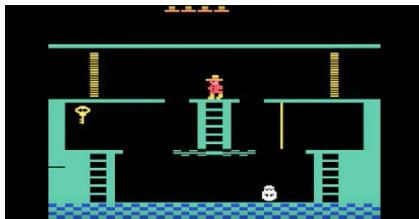
2. Examples that are captured by the Bellman rank framework

## Setting

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

State space  $S_h$  is extremely large:

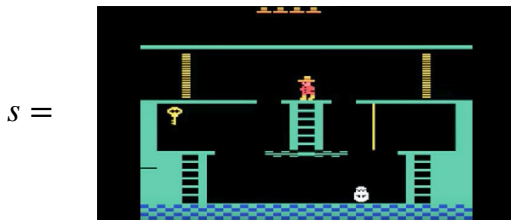
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Not acceptable:  $\text{poly}(|S|)$

Need to generalize via (nonlinear) function approximation

## Let's set up function class in RL setting

We will consider **Q function class**

$$\mathcal{F} \subset S \times A \mapsto [0,1] \quad [0, H]$$

$$f \in \mathcal{F}$$

$$f(s, a).$$

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

$\rightarrow \otimes$   
 $V^* \in \mathcal{V}$



## **Learning Goal:**

We will do PAC in this lecture rather than regret.

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Given approximation error  $\epsilon$  and failure prob  $\delta$ ,  
can we learn  $\epsilon$  *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?

$$g: S \times A \rightarrow [0, H]$$

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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Hence, any  $g$  such that  $\mathcal{E}(g; f, h) \neq 0$ , is an incorrect  $Q^*$  approximator

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Hence, any  $g$  such that  $\mathcal{E}(g; \pi, h) \neq 0$ , is an incorrect  $Q^*$  approximator

# The Q / V-Bellman rank

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

	$g$	$f$			
$\pi_f$	$\mathcal{E}_{g,f,h}$	$\mathcal{E}_{f,f,h}$			



## The Q / V-Bellman rank

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

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

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

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

$$w := T_h(\theta)$$

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$T_h(\theta)^\top \phi(s_h, a_h)$

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Note linear Bell-completion captures tabular / linear mdp already

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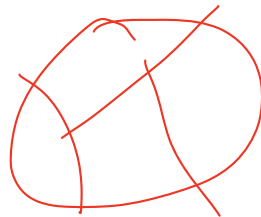
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As we will see, linear  $Q^*$  &  $V^*$  is learnable, and recall linear  $Q^*$  is not...

## $Q^*$ - state abstraction

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

$$Q^*(s_1, a) = Q^*(s_2, a), \forall a, \text{ if } \xi(s_1) = \xi(s_2)$$



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

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

$$\begin{aligned} \phi(s, a) &\in \mathbb{R}^{|Z||A|} \\ \psi(s) &\in \mathbb{R}^{|Z|} \end{aligned}$$

## Low-rank MDP

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

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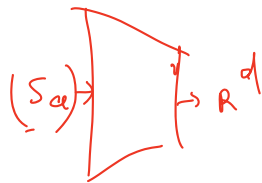
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Define representation class  $\Phi$ , with  $\phi^* \in \Phi$

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$$Q^* \in \mathcal{F}$$

$$\Phi: S \times A \rightarrow \mathbb{R}^d$$



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$$V_g = \max_a g(s, a)$$
$$\pi_g = \operatorname{argmax}_a g(s, a)$$

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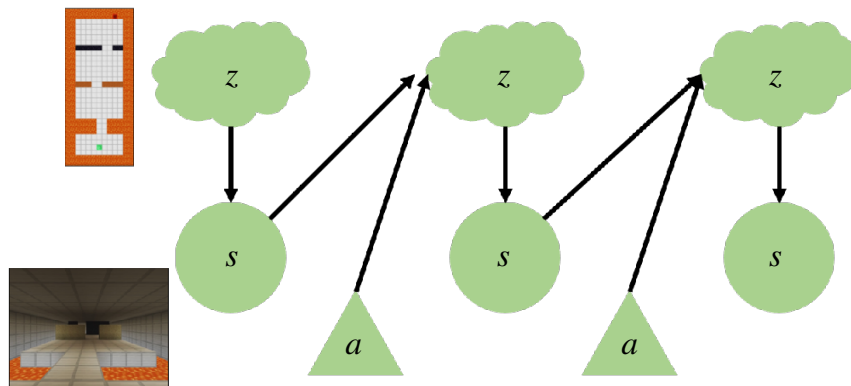
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$X_h(f)$

$W_h(g)$

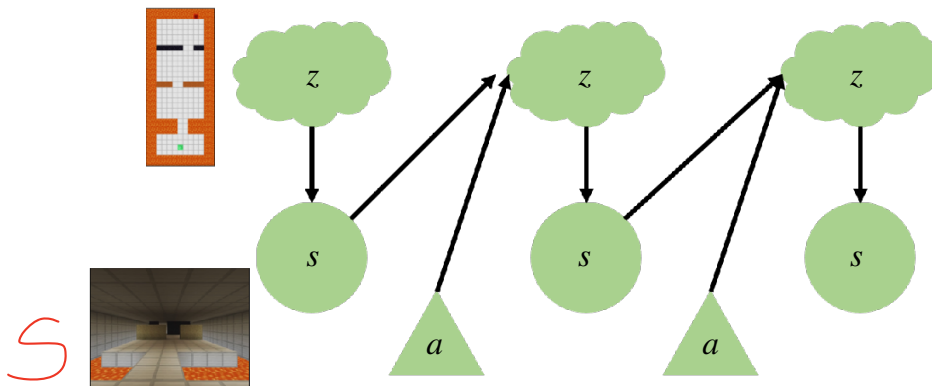
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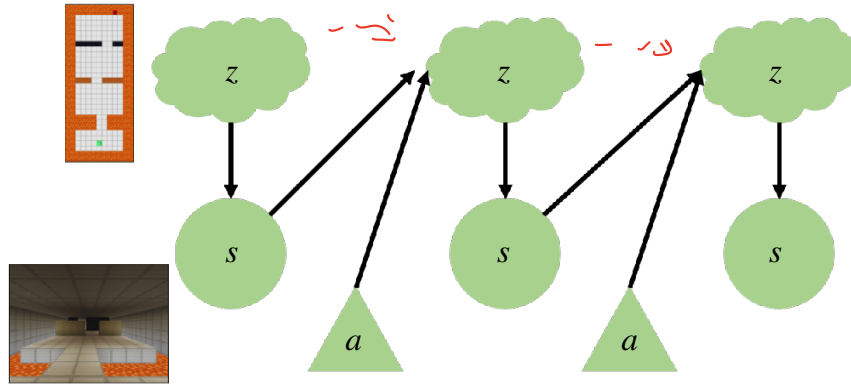
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V-Bellman rank = Number of latent states



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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  $\epsilon$  near optimal policy w/ # of samples

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