

Autonomous and Adaptive Systems

Monte Carlo Methods

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Monte Carlo Methods

- ▶ Monte Carlo methods are ways of solving the reinforcement learning problems based on averaging the sample returns.
- ▶ We focus on episodic tasks.
 - ▶ Only on the completion of episodes are values estimates and policies changed.
- ▶ Monte Carlo methods sample and average *returns* for each state-action pair much like the multi-armed bandits methods and average *rewards* for each action.
 - ▶ However, we now consider *multiple states*; and
 - ▶ The return after taking an action in one state depends on the actions taken in later states in the same episodes.
 - ▶ In other words: this is the “full” reinforcement learning problem.

Monte Carlo Methods

- ▶ If you have the full knowledge of the MDP you can *compute* the value functions (see Bellman equation, dynamic programming).
- ▶ We assume that we do not have full knowledge of the underlying MDP.
 - ▶ This is the case in general because the underlying dynamics and characteristics of the system are unknown (e.g., robot exploration) or because the system is too complex (e.g., games).
- ▶ Since we do not have full knowledge, we need to *learn* the values functions.

Monte Carlo Methods

- ▶ We consider three problems:
 - ▶ The *prediction problem*: the estimation of v_π and q_π for a fixed policy π .
 - ▶ The *policy improvement problem*: the estimation of v_π and q_π while trying at the same time to improve the policy π .
 - ▶ The *control problem*: the estimation of an optimal policy π_* .

Monte Carlo Prediction

- ▶ Goal: learning the state-value function for a given policy.
 - ▶ Recall: the value of a state is the expected return (expected cumulative future discounted reward) from that state.
- ▶ Obvious/simple solution: average the returns observed after visiting that state. As more returns are observed, the average should converge to the expected value.

Monte Carlo Prediction

- ▶ More formally: we want to estimate $v_{\pi}(s)$, the value of a state s under policy π , given a set of episodes obtained by following π and passing through s .
- ▶ Each occurrence of a state s in an episode is called a *visit* to s .
- ▶ A state s can be visited multiple times.
- ▶ The first time a state s is visited in an episode is called the first visit to s .
- ▶ The *first-visit Monte Carlo method* estimates $v_{\pi}(s)$ as the average of the returns following first visits to s , whereas the *every-visit Monte Carlo method* averages the returns following all the visits to s .

First-visit Monte Carlo Prediction

Input: a policy π to be evaluated

Initialise:

$V(s) \in \mathbb{R}$ arbitrarily for all $s \in \mathcal{S}$

$Returns(s) \leftarrow$ empty list for all $s \in \mathcal{S}$

Loop forever (for each episode):

Generate an episode following π : $S_0, A_0, R_1, S_1, A_1, R_2, \dots, S_{T-1}, A_{T-1}, R_T$

$G \leftarrow 0$

Loop for each step of episode $t = T - 1, T - 2, \dots, 0$:

$G \leftarrow \gamma G + R_{t+1}$

If S_t does not appear in S_0, S_1, \dots, S_{t-1} :

Append G to $Returns(S_t)$

$V(S_t) \leftarrow average>Returns(S_t)$

Multi-visit Monte Carlo Prediction

- ▶ Every-visit Monte Carlo would be the same except without the check for S_t having occurred earlier in the episode.
- ▶ Both first-visit Monte Carlo and every-visit Monte Carlo converge to $v_{\pi}(s)$ as the number of visits (or first visits) to s goes to infinity.



https://www.youtube.com/watch?time_continue=70&v=Do1MBeEmk6Q

Credit: Forbes



<https://www.youtube.com/watch?v=Oyl2wJ6F8r0>

Monte Carlo Estimation of Action Values

- ▶ The estimation of a state value makes sense when you have a model of the system.
 - ▶ With a model, state values alone are sufficient to determine a policy.
 - ▶ Without a model, it is necessary to estimate the value of each action in order for the value to be useful in suggesting a policy.
- ▶ The policy evaluation problem for action values is to estimate $q_{\pi}(s, a)$, the expected return when starting in state s , taking action a and then following policy π .
 - ▶ Remember we assume that the policy π is fixed.

Monte Carlo Estimation of Action Values

- ▶ The methods for the Monte Carlo estimation of action values are essentially the same as those presented for state value, but now we talk about visits to the state-action pair instead of to a state.
- ▶ A state-action pair s, a is said to be visited in an episode if the state s is visited and the action a is taken in it.
- ▶ The first-visit method Monte Carlo method averages the returns following the first time in each episode that the state was visited and the action was selected.

Maintaining Exploration

- ▶ But there is a problem: many state-action pairs might never be visited.
- ▶ If π is a deterministic policy, then in following π , we will observe returns only for one of the actions of each state.
 - ▶ No return to average -> no improvement with experience.
 - ▶ We cannot compare alternatives, because no alternatives are explored.
- ▶ To compare alternatives, we need to estimate the value of all the actions from each state, not only the the one we currently prefer (according to our policy).
- ▶ How can we address this problem?

Maintaining Exploration

- ▶ This is the general problem of *maintaining exploration*.
- ▶ One way to do this is to have the episodes starting in a state-action pair and that every pair has non-zero probability of being selected as start.
- ▶ This ensures that asymptotically (infinite number of episodes), all the state-action pairs will be visited an infinite number of times.

On-policy and Off-policy Exploration

- ▶ The method described above is useful, but it cannot be applied in general.
 - ▶ Think about the case for example where you have exploration with the environment. You cannot start by “jumping” to a certain state-action pair at the beginning.
- ▶ The most common alternative is to ensure that all the state-action pairs are explored anyway.
- ▶ We need to explore these states, *not following* the current policy (for example with a stochastic policy). In other words, the exploration is not performed *on-policy* as done until now in this lecture, but *off-policy*.
 - ▶ Various methods are possible: Off-policy prediction via Importance Sampling (not covered in this module - see Sutton and Barto Chapter 5.5).

Policy Improvement

- ▶ We will focus now back on on-policy exploration, i.e., the policy is used to make decisions and to explore the various states.
- ▶ Until now we assumed that the policy was fixed.
- ▶ However, the policy itself can be *improved* while learning the value functions and, potentially, we might have to aim at obtaining an optimal policy.
- ▶ Methods used for improving a policy in order to reach the optimal policy are usually referred to as *Monte Carlo control*.

Policy Improvement

- ▶ Remember until now we assumed that the policy was fixed.
 - ▶ Given that policy, we estimate the value functions.
- ▶ Now we consider how to improve the policy starting from an *on-policy method*.
 - ▶ The policy that we use to make decisions is that we are trying to improve. We do not use a separate policy to explore the state-action pairs (that would be an *off-policy method*).
- ▶ Policy improvement is done by making the policy greedy with respect to the current value functions.

Policy Improvement

- ▶ In this case we have an action-value function.
 - ▶ No model is needed to construct the greedy policy.
- ▶ For any action-value function q , the corresponding greedy policy is the one that, for each $s \in \mathcal{S}$, deterministically chooses an action with maximal action-value:

$$\pi(s) \leftarrow \arg \max_a Q(s, a)$$

- ▶ We have formal results that ensures that this process of policy improvement leads to optimal policy (usually referred to Monte Carlo control).

Monte Carlo Control without Exploring Starts

- ▶ An alternative method for Monte Carlo control (i.e., to achieve the optimal policy) is to use an ϵ -greedy approach.
- ▶ Most of the time the action that has the maximal estimated action value is chosen but with a probability ϵ an action is chosen at random.
 - ▶ This means that all non-greedy actions are given the minimal probability of selection $\frac{\epsilon}{|\mathcal{A}(s)|}$ is given to all the non-greedy actions.
- ▶ Following these mechanism, it can be guaranteed that we will have an improvement of the policy (policy improvement theorem).

Monte Carlo Prediction with Exploring Starts

Initialise:

$\pi(s) \in \mathcal{A}(s)$ arbitrarily for all $s \in \mathcal{S}$

$Q(s, a) \in \mathbb{R}$ arbitrarily for all $s \in \mathcal{S}, a \in \mathcal{A}(s)$

$Returns(s, a) \leftarrow$ empty list for all $s \in \mathcal{S}, a \in \mathcal{A}(s)$

Loop forever (for each episode):

Choose $S_0 \in \mathcal{S}, A_0 \in \mathcal{A}(S_0)$ randomly

Generate an episode from S_0, A_0 following π : $S_0, A_0, R_1, S_1, A_1, R_2, \dots, S_{T-1}, A_{T-1}, R_T$

$G \leftarrow 0$

Loop for each step of episode $t = T - 1, T - 2, \dots, 0$:

$G \leftarrow \gamma G + R_{t+1}$

If S_t does not appear $S_0, A_0, R_1, A_1, R_2, \dots, S_{T-1}, A_{T-1}$:

Append G to $Returns(S_t, A_t)$

$Q(S_t, A_t) \leftarrow average(Returns(S_t, A_t))$

$\pi(S_t) \leftarrow \arg \max_a Q(S_t, a)$

References

- ▶ Chapter 5 of Sutton and Barto. Introduction to Reinforcement Learning. Second Edition. MIT Press. 2018.