

Markov Decision Processes

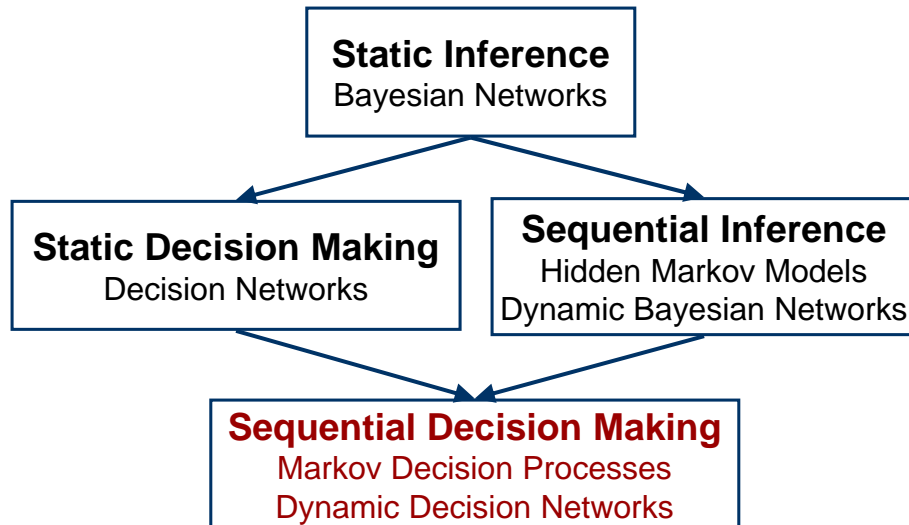
[RN2] Sec 17.1, 17.2, 17.4, 17.5
[RN3] Sec 17.1, 17.2, 17.4

CS 486/686
University of Waterloo
Lecture 13: October 23, 2012

Outline

- Markov Decision Processes
- Dynamic Decision Networks

Sequential Decision Making



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Sequential Decision Making

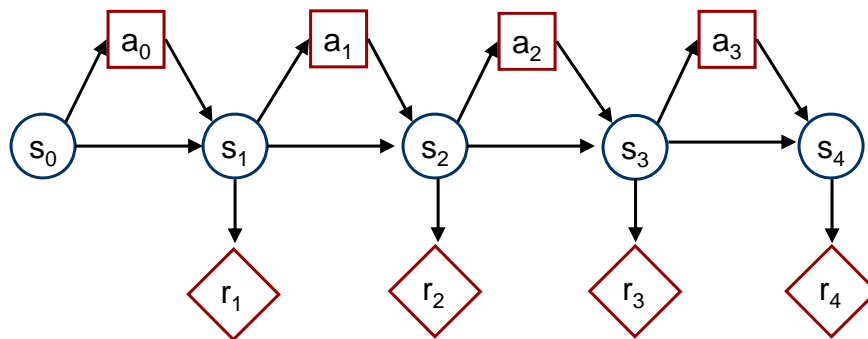
- Wide range of applications
 - Robotics (e.g., control)
 - Investments (e.g., portfolio management)
 - Computational linguistics (e.g., dialogue management)
 - Operations research (e.g., inventory management, resource allocation, call admission control)
 - Assistive technologies (e.g., patient monitoring and support)

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Markov Decision Process

- Intuition: Markov Process with...
 - Decision nodes
 - Utility nodes



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Stationary Preferences

- Hum... but why many utility nodes?
- $U(s_0, s_1, s_2, \dots)$
 - Infinite process \rightarrow infinite utility function
- Solution:
 - Assume stationary and additive preferences
 - $U(s_0, s_1, s_2, \dots) = \sum_{t} R(s_t)$

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Discounted/Average Rewards

- If process infinite, isn't $\sum_t R(s_t)$ infinite?
- Solution 1: **discounted rewards**
 - Discount factor: $0 \leq \gamma \leq 1$
 - Finite utility: $\sum_t \gamma^t R(s_t)$ is a geometric sum
 - γ is like an inflation rate of $1/\gamma - 1$
 - Intuition: prefer utility sooner than later
- Solution 2: **average rewards**
 - More complicated computationally
 - Beyond the scope of this course

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Markov Decision Process

- Definition
 - Set of states: S
 - Set of actions (i.e., decisions): A
 - Transition model: $\Pr(s_t | a_{t-1}, s_{t-1})$
 - Reward model (i.e., utility): $R(s_t)$
 - Discount factor: $0 \leq \gamma \leq 1$
 - Horizon (i.e., # of time steps): h
- Goal: **find optimal policy**

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Inventory Management

- Markov Decision Process
 - States: **inventory levels**
 - Actions: **{doNothing, orderWidgets}**
 - Transition model: **stochastic demand**
 - Reward model: **Sales - Costs - Storage**
 - Discount factor: **0.999**
 - Horizon: **∞**
- Tradeoff: **increasing supplies decreases odds of missed sales but increases storage costs**

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Policy

- Choice of action at each time step
- Formally:
 - Mapping from states to actions
 - i.e., $\delta(s_t) = a_t$
 - Assumption: **fully observable states**
 - Allows a_t to be chosen only based on current state s_t . Why?

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Policy Optimization

- Policy evaluation:
 - Compute expected utility
 - $EU(\delta) = \sum_{t=0}^h \gamma^t \Pr(s_t | \delta) R(s_t)$
- Optimal policy:
 - Policy with highest expected utility
 - $EU(\delta) \leq EU(\delta^*)$ for all δ

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Policy Optimization

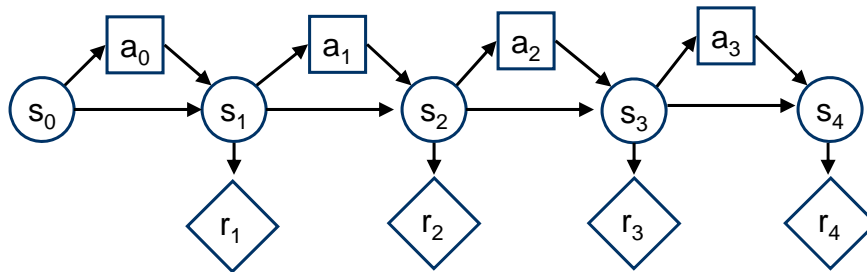
- Three algorithms to optimize policy:
 - Value iteration
 - Policy iteration
 - Linear Programming
- Value iteration:
 - Equivalent to variable elimination

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Value Iteration

- Nothing more than variable elimination
- Performs dynamic programming
- Optimize decisions in reverse order

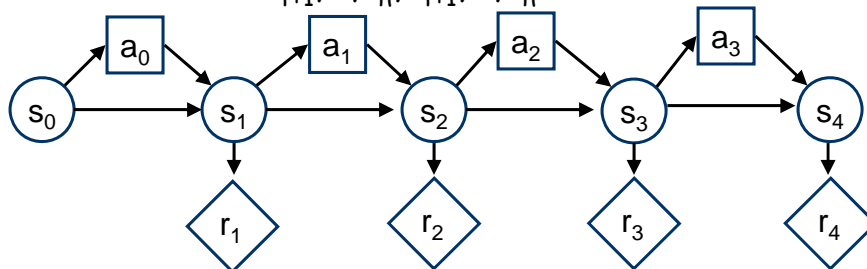


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Value Iteration

- At each t , starting from $t=h$ down to 0 :
 - Optimize a_t : $EU(a_t | s_t)$?
 - Factors: $\Pr(s_{i+1} | a_i, s_i), R(s_i)$, for $0 \leq i \leq h$
 - Restrict s_t
 - Eliminate $s_{t+1}, \dots, s_h, a_{t+1}, \dots, a_h$



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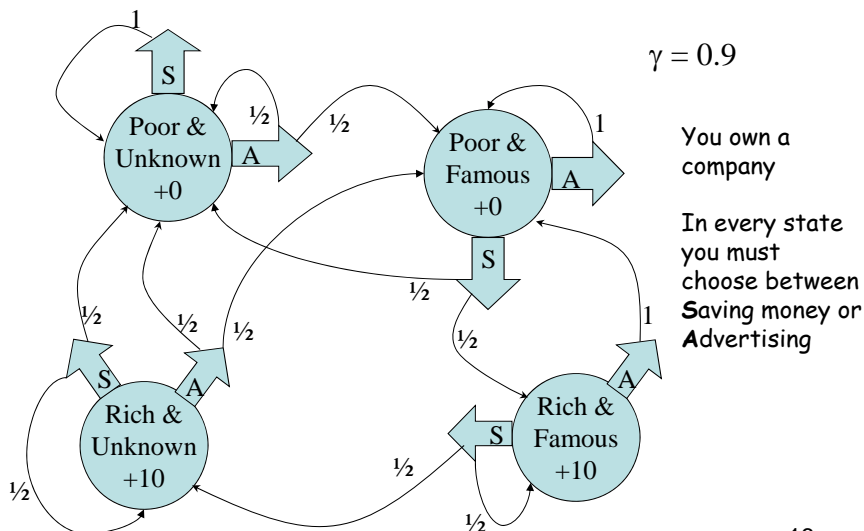
Value Iteration

- Value when no time left:
 - $V(s_h) = R(s_h)$
- Value with one time step left:
 - $V(s_{h-1}) = \max_{a_{h-1}} R(s_{h-1}) + \gamma \sum_{s_h} \Pr(s_h | s_{h-1}, a_{h-1}) V(s_h)$
- Value with two time steps left:
 - $V(s_{h-2}) = \max_{a_{h-2}} R(s_{h-2}) + \gamma \sum_{s_{h-1}} \Pr(s_{h-1} | s_{h-2}, a_{h-2}) V(s_{h-1})$
- ...
- **Bellman's equation:**
 - $V(s_t) = \max_{a_t} R(s_t) + \gamma \sum_{s_{t+1}} \Pr(s_{t+1} | s_t, a_t) V(s_{t+1})$
 - $a_t^* = \operatorname{argmax}_{a_t} R(s_t) + \gamma \sum_{s_{t+1}} \Pr(s_{t+1} | s_t, a_t) V(s_{t+1})$

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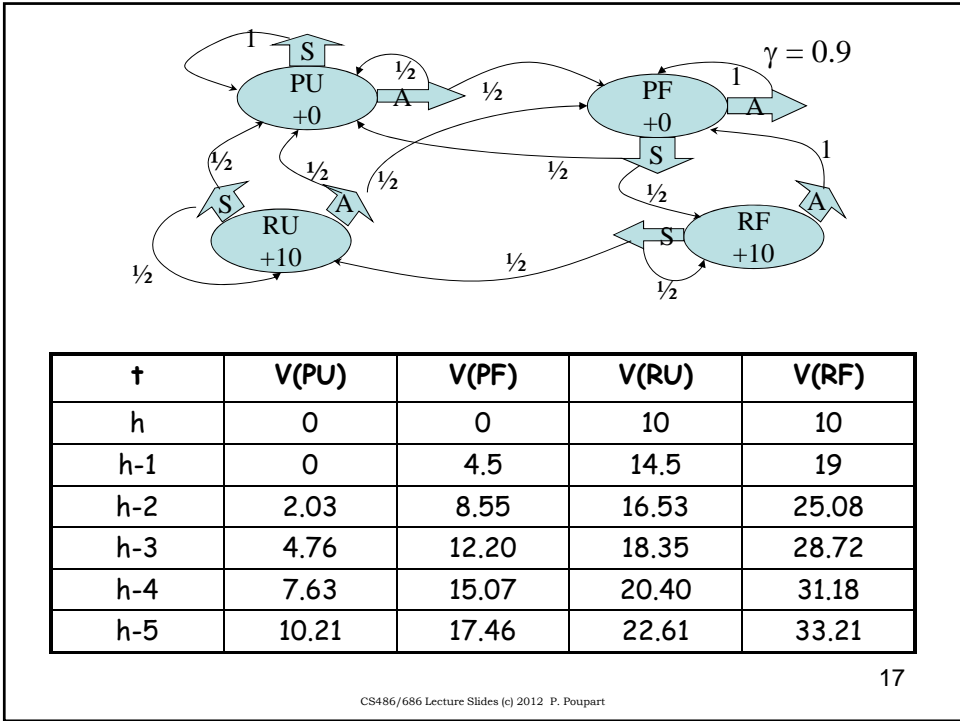
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A Markov Decision Process



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Finite Horizon

- When h is finite,
- **Non-stationary optimal policy**
- Best action different at each time step
- Intuition: best action varies with the amount of time left

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Infinite Horizon

- When h is infinite,
- **Stationary optimal policy**
- Same best action at each time step
- Intuition: same (infinite) amount of time left at each time step, hence same best action
- **Problem:** value iteration does an infinite number of iterations...

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Infinite Horizon

- Assuming a discount factor γ , after k time steps, rewards are scaled down by γ^k
- For large enough k , rewards become insignificant since $\gamma^k \rightarrow 0$
- Solution:
 - pick large enough k
 - run value iteration for k steps
 - Execute policy found at the k^{th} iteration

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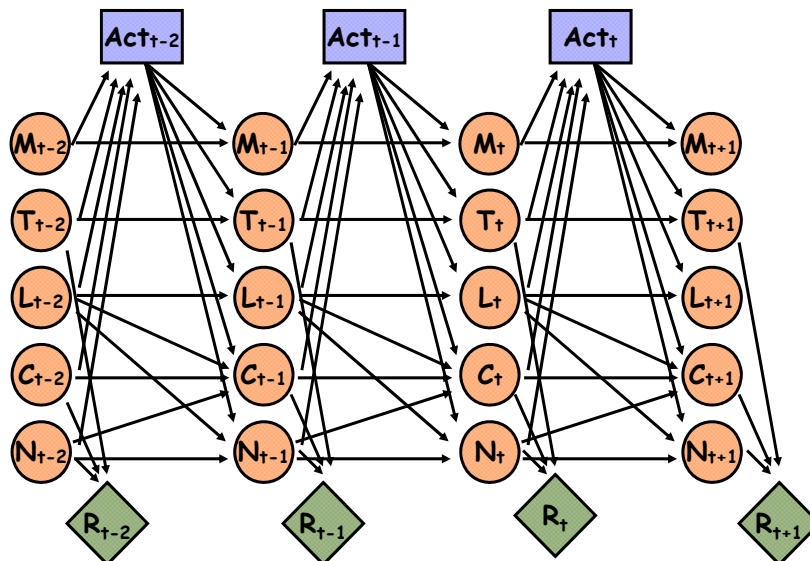
Computational Complexity

- Space and time: $O(k|A||S|^2)$ ☺
 - Here k is the number of iterations
- But what if $|A|$ and $|S|$ are defined by several random variables and consequently exponential?
- Solution: exploit conditional independence
 - **Dynamic decision network**

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Dynamic Decision Network



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Dynamic Decision Network

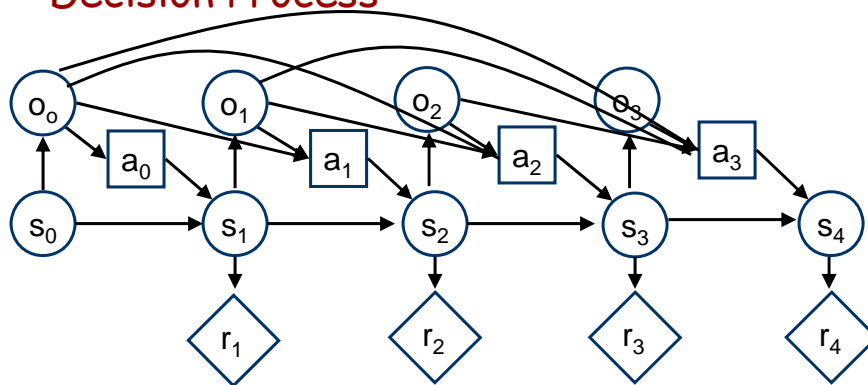
- Similarly to dynamic Bayes nets:
 - Compact representation 😊
 - Exponential time for decision making 😞

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Partial Observability

- What if states are not fully observable?
- Solution: **Partially Observable Markov Decision Process**



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Partially Observable Markov Decision Process (POMDP)

- Definition
 - Set of states: S
 - Set of actions (i.e., decisions): A
 - Set of observations: O
 - Transition model: $\Pr(s_t | a_{t-1}, s_{t-1})$
 - Observation model: $\Pr(o_t | s_t)$
 - Reward model (i.e., utility): $R(s_t)$
 - Discount factor: $0 \leq \gamma \leq 1$
 - Horizon (i.e., # of time steps): h
- Policy: mapping from past obs. to actions

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POMDP

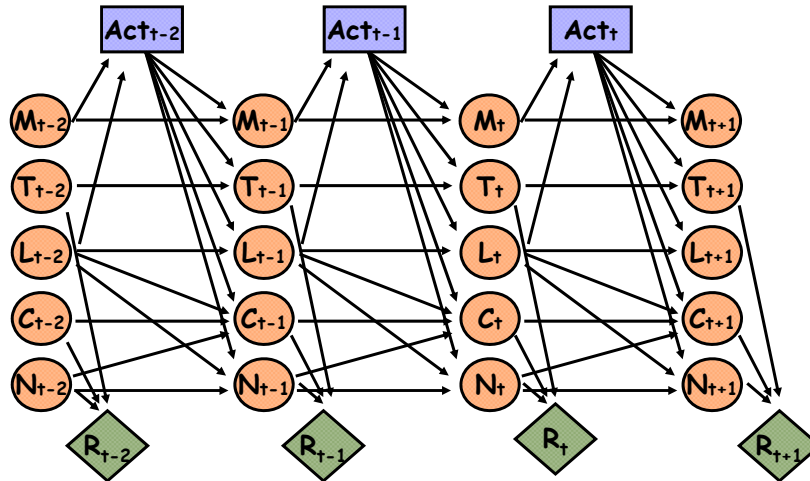
- Problem: action choice generally depends on **all previous observations...**
- Two solutions:
 - Consider only policies that depend on a finite history of observations
 - Find **stationary sufficient statistics** encoding relevant past observations

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Partially Observable DDN

- Actions do not depend on all state variables



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Policy Optimization

- Policy optimization:
 - Value iteration (variable elimination)
 - Policy iteration
- POMDP and PODDN complexity:
 - Exponential in $|O|$ and k when action choice depends on all previous observations ☹
 - In practice, good policies based on subset of past observations can still be found

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COACH project

- Automated prompting system to help elderly persons wash their hands
- IATSL: Alex Mihailidis, Pascal Poupart, Jennifer Boger, Jesse Hoey, Geoff Fernie and Craig Boutilier



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Aging Population

- Dementia
 - Deterioration of intellectual faculties
 - Confusion
 - Memory losses (e.g., Alzheimer's disease)
- Consequences:
 - Loss of autonomy
 - Continual and expensive care required



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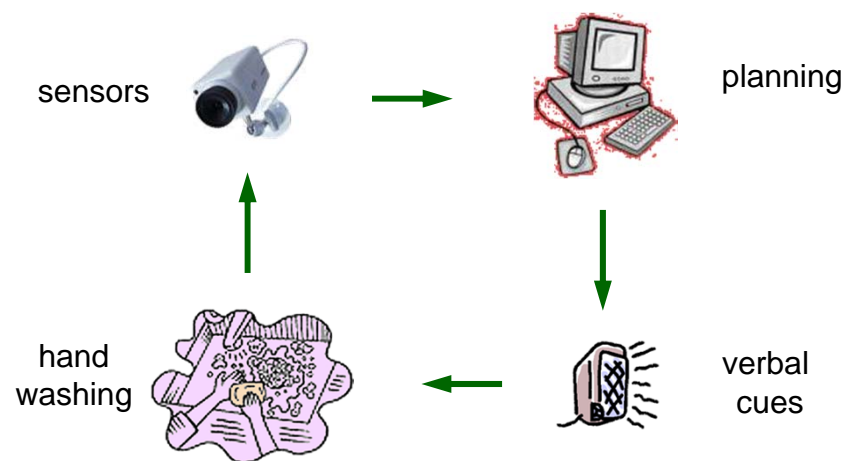
Intelligent Assistive Technology

- Let's facilitate aging in place
- Intelligent assistive technology
 - Non-obtrusive, yet pervasive
 - Adaptable
- Benefits:
 - Greater autonomy
 - Feeling of independence

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System Overview



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Prompting Strategy

- Sequential decision problem
 - Sequence of prompts
- Noisy sensors & imprecise actuators
 - Noisy image processing, uncertain prompt effects
- Partially unknown environment
 - Unknown user habits, preferences and abilities
- Tradeoff between complex concurrent goals
 - Rapid task completion vs greater autonomy
- Approach: Partially Observable Markov Decision Processes (POMDPs)

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POMDP components

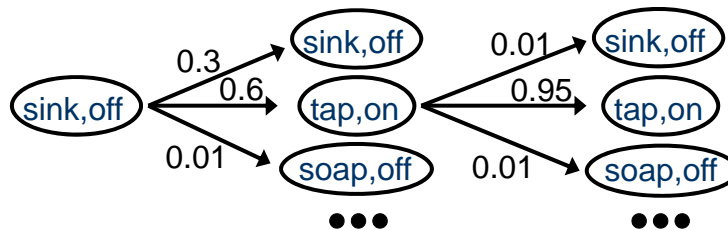
- State set $\mathbf{S} = \text{dom}(\text{HL}) \times \text{dom}(\text{WF}) \times \text{dom}(\text{D}) \times \dots$
 - Hand Location $\in \{\text{tap}, \text{water}, \text{soap}, \text{towel}, \text{sink}, \text{away}, \dots\}$
 - Water Flow $\in \{\text{on}, \text{off}\}$,
 - Dementia $\in \{\text{high}, \text{low}\}$, etc.
- Observation set $\mathbf{O} = \text{dom}(\text{C}) \times \text{dom}(\text{FS})$
 - Camera $\in \{\text{handsAtTap}, \text{handsAtTowel}, \dots\}$
 - Faucet sensor $\in \{\text{waterOn}, \text{waterOff}\}$
- Action set \mathbf{A}
 - DoNothing, CallCaregiver, Prompt $\in \{\text{turnOnWater}, \text{rinseHands}, \text{useSoap}, \dots\}$

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POMDP components

- Transition function $\Pr(s'|s,a)$
- Observation function $\Pr(o|s)$



- Reward function $R(s,a)$
 - Task completed $\rightarrow +100$
 - Call caregiver $\rightarrow -30$
 - Each prompt $\rightarrow -1, -2$ or -3

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Next Class

- Machine Learning
- Decision Trees

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