



## ICLR 2024

# PRIORITIZED SOFT Q-DECOMPOSITION FOR LEXICOGRAPHIC REINFORCEMENT LEARNING

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#### **MOTIVATION**

- Improve RL's sample-efficiency by means of knowledge transfer
- We assume a fixed MDP:  $\langle \mathcal{S}, \mathcal{A}, \mathbf{r}, p, \gamma 
  angle$  with continuous  $\mathbf{a} \in \mathbb{R}^d$ 
  - Multiple "subtask" reward functions  $\mathbf{r} = [r_1, \dots, r_n]$
  - Solve subtasks seperately, transfer knowledge between tasks
- Challenges:
  - Q-Decomposition:  $Q_{\Sigma}^* \neq Q_1^* + Q_2^*$  (Russel & Zimdars 2003)
  - Reward engineering: Incompatible subtasks?

#### LEXICOGRAPHIC REINFORCEMENT LEARNING

- Multi-objective RL  $\langle \mathcal{S}, \mathcal{A}, \mathbf{r}, p, \gamma \rangle$  with priority ordering over subtasks
  - Notation:  $r_1 \succ r_2 \succ \cdots \succ r_n$
  - Priority is set by practitioner
  - Priority resolves subtask conflicts
- Knowledge transfer?

## PRIORITIZED SOFT Q-DECOMPOSITION: INTUITION

- Lexicographic RL problems with continuous actions
- Knowledge transfer from higher to lower priority subtasks
  - Learn  $r_1$  once
  - ullet Transfer  $\pi_1^*$  and  $Q_1^*$  to n-1 lower-priority subtasks
  - Lower-priority subtasks are constrained to keeping higher-priority subtask near-optimal

## PRIORITIZED SOFT Q-DECOMPOSITION: TECHNICAL

- ullet Assume access to already-learned  $Q_1^*$  for  $r_1$
- ullet Define performance threshold  $arepsilon_1$  for  $Q_1^*$

$$ullet \max_{\pi_2} J(\pi_2) = \mathbb{E}_{( au \sim \pi_2)} igg[ \sum_{t=0}^\infty \gamma^t r_2(\mathbf{s}_t, \mathbf{a}_t) igg]$$

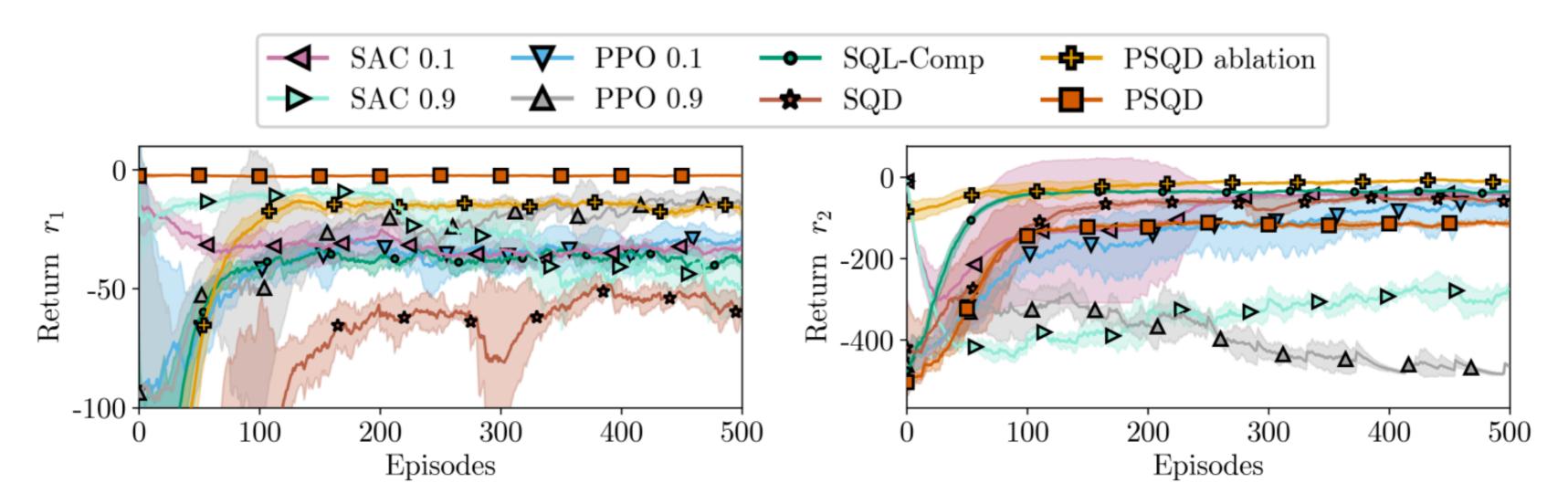
• subject to: 
$$\max_{\mathbf{a}' \in \mathcal{A}} Q_1^*(\mathbf{s}_t, \mathbf{a}') - Q_1^*(\mathbf{s}_t, \pi_2(\mathbf{s}_t)) \leq \varepsilon$$
 best Q-val in  $\mathbf{s}$ 

$$\max_{\mathbf{a}' \in \mathcal{A}} Q_i^*(\mathbf{s}_t, \mathbf{a}') - Q_i^*(\mathbf{s}_t, \pi_n(\mathbf{s}_t)) \leq \varepsilon_i, \ \forall i \in \{1, \dots, n-1\}$$

• Knowledge transfer via constraints on already-learned Q-functions

### **RESULTS**

- High-priority subtask  $r_1$ : Obstacle avoidance
- Low-priority subtask  $r_2$ : Goal navigation



## **THANK YOU**

#### Prioritized Soft Q-Decomposition for Lexicographic Reinforcement Learning

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https://github.com/frietz58/psqd/