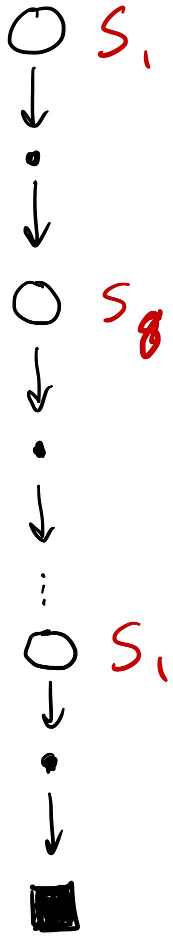

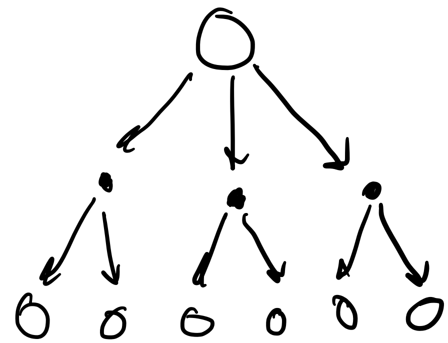

Bellman eqn. for V_π,
Dynamic programming

Monte Carlo
est. of V_π

Sample of return:

$$G_{s_t} = \sum_{i=t}^{T-1} r_i \implies V(s) = E\left[G_{s_t}\right]$$

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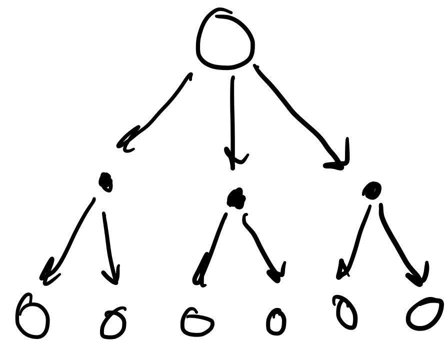

Bellman eqn. for V_π,
Dynamic programming

MC:
- only sampled transitions
- All the way to end of episode
- no bootstrapping

DP:
- All possible transitions
- only one step
- bootstrapping

Sample of return:

$$G_{s_t} = \sum_{i=t}^{T-1} r_i \quad \Longrightarrow \quad V(s) = E\left[G_{s_t}\right]$$

$G_i^{s,\pi}$: i^{th} return starting from state s, collected from policy π

On policy prediction:

$$V_\pi(s) = \frac{1}{N} \sum_{i=1}^{N} G_i^{s,\pi}$$

$$Q_\pi(s,a) = \frac{1}{N} \sum_{i=1}^{N} G_i^{s,a,\pi}$$

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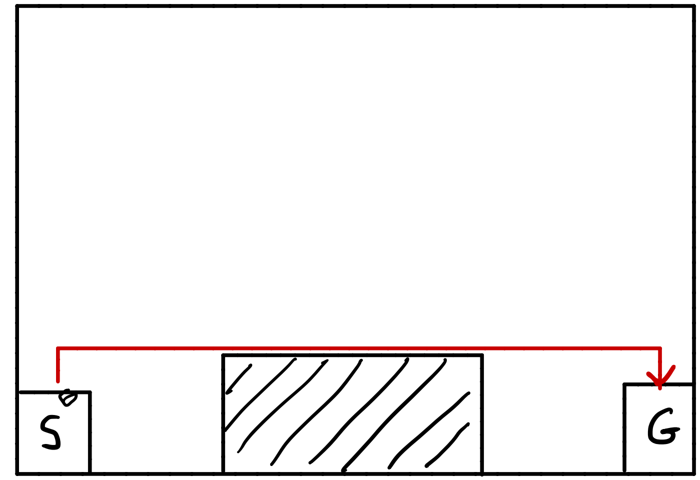

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prediction

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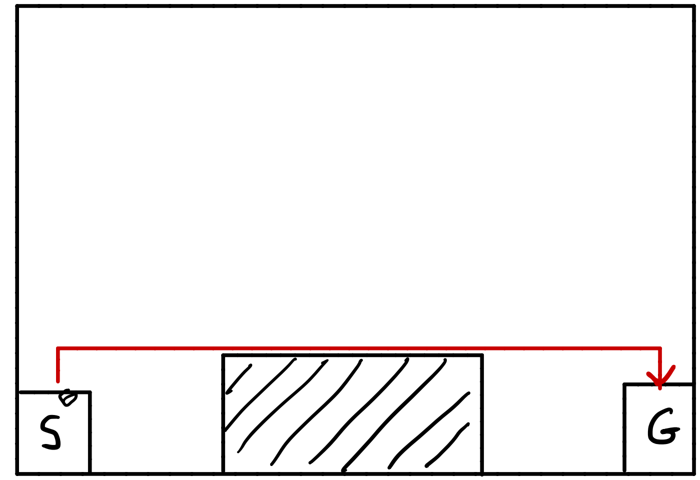

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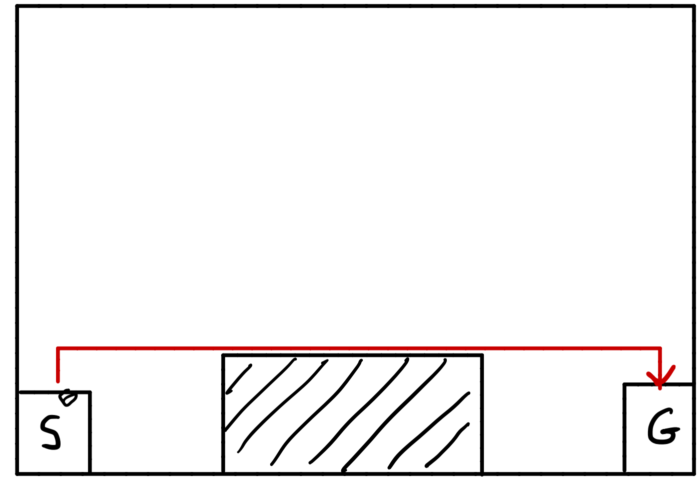

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Consider: On-policy control vs. off-policy control w/ ϵ-greedy exploration

What are $\underbrace{V_\star \text{ and } \pi_\star}_{\text{off-policy}}$ vs. $\underbrace{\tilde{V}_\star \text{ and } \tilde{\pi}_\star}_{\text{on-policy}}$?

Safe off policy evaluation:

Return probabilistic lower bound V_π^{lb} such that:

$V_\pi > V_\pi^{lb}$ with prob. $1-\delta$ Given: π, δ, data from π_b

without ever running policy π!

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$$\downarrow$$

$$V_\pi \geq \frac{1}{n}\sum_{i=1}^{n} G_i^{\pi_b} \cdot e_i^{\pi,\pi_b} - G_{max}\sqrt{\frac{\log(1/\delta)}{2n}} \qquad \text{for } 0 \leq G_i \leq G_{max}$$

Given returns $G_1 \cdots G_n$ from policy π_b AND $\rho_i = \prod_{k=t_i}^{T_i-1} \frac{\pi(A_k|S_k)}{\pi_b(A_k|S_k)}$ THEN: $V_\pi(s) =$

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PDIS:

$$\frac{1}{n} \sum \tilde{G}_i \text{, where:}$$

$$\tilde{G}_i = \rho_{1:1} R_1 + \gamma \rho_{1:2} R_2 + \dots + \gamma^{n-1} \rho_{1:t} R_t$$

and

$$\rho_{a:b} = \prod_{k=a}^{b} \frac{\pi(A_k|S_k)}{\pi_b(A_k|S_k)}$$