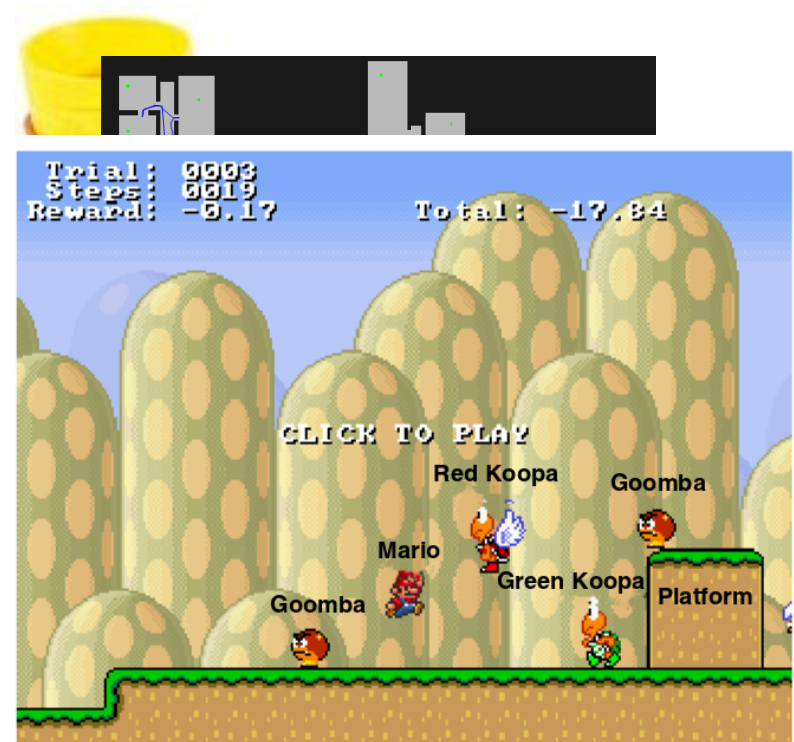
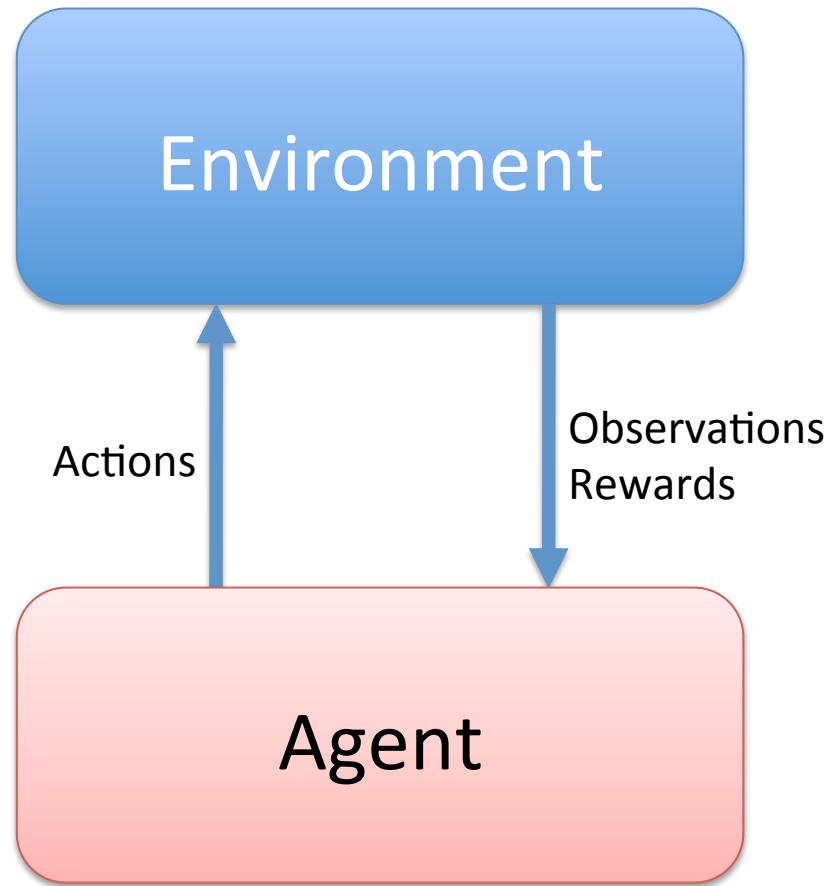


Soar-RL and Reinforcement Learning

Introducing talks by
Shiwali Mohan, Mitchell Keith Bloch
& Nick Gorski

Reinforcement Learning



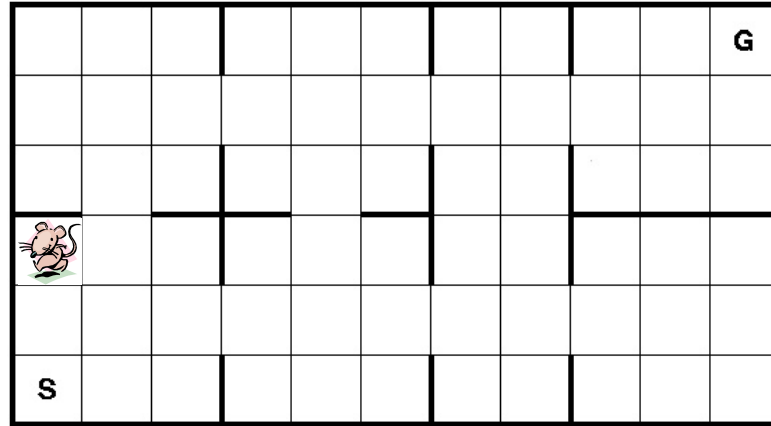
Value in Reinforcement Learning

- *Value*: future expected reward
- RL goal: maximize value
- RL agent: select actions with highest value

State and Observability

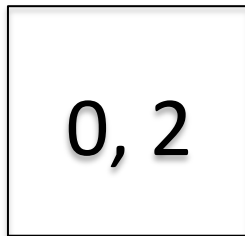
Agent observes a representation of world state

Can be Markovian or partial

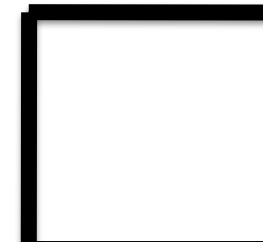


Agent doesn't observe semantics of task

Must learn the meanings of symbols and actions



Markovian representation

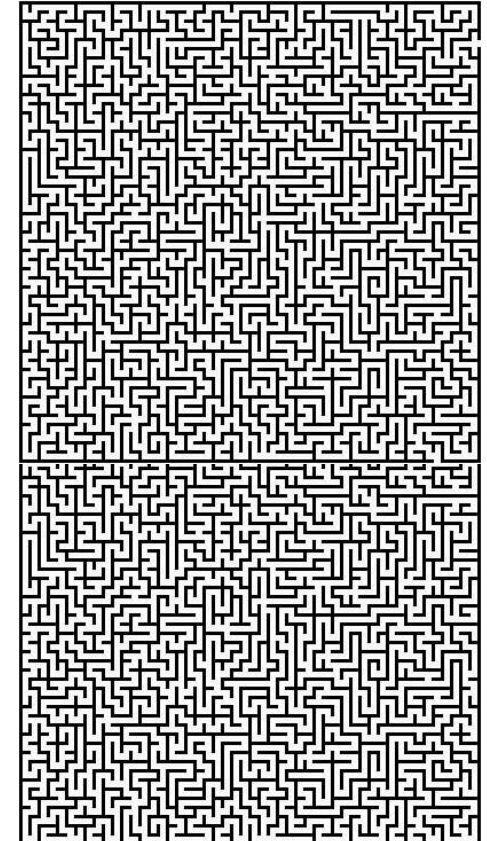
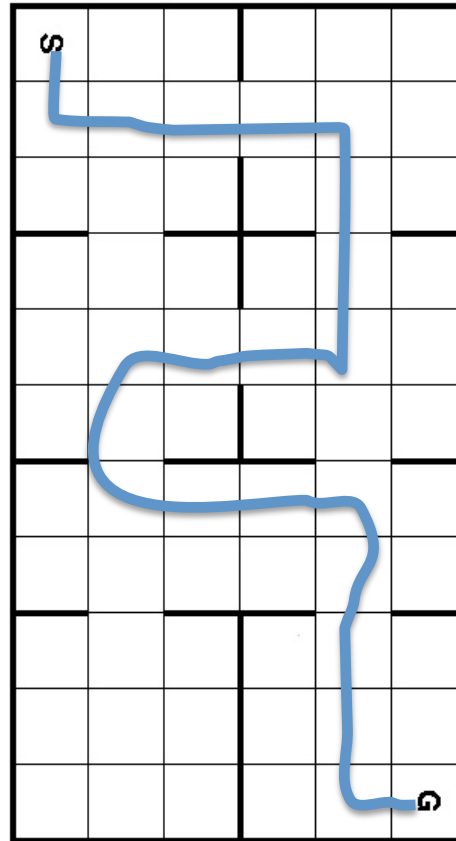


Partial representation

Why Reinforcement Learning Is Hard

ENGLISH OPENING

White	Black	White	Black
Vitiugov	Wang	Vitiugov	Wang
1 c4	e5	20 a4	a6
2 Nc3	Nf6	21 Nd2	Bf8
3 Nf3	Nc6	22 Nc4	b5
4 g3	d5	23 ab5	ab5
5 cd5	Nd5	24 Nd2	Nb6
6 Bg2	Nb6	25 Nf3	Na4
7 0-0	Be7	26 Qc2	c5
8 a3	0-0	27 Be5	cb4
9 b4	Be6	28 Qb3	Nc3
10 d3	Nd4	29 Re1	Qd7
11 Bb2	Nf3	30 Kg2	Qf5
12 Bf3	c6	31 Ra7	Re5
13 Ne4	Nd7	32 Ne5	Qe5
14 Qc2	Bd5	33 Qf7	Kh8
15 Bc3	Re8	34 Rea1	Qf6
16 Rfd1	Rc8	35 Qb3	Ne2
17 Qb2	Bf8	36 R1a6	Qf5
18 Nd2	Bf3	37 Re-	signs
19 Nf3	Bd6		

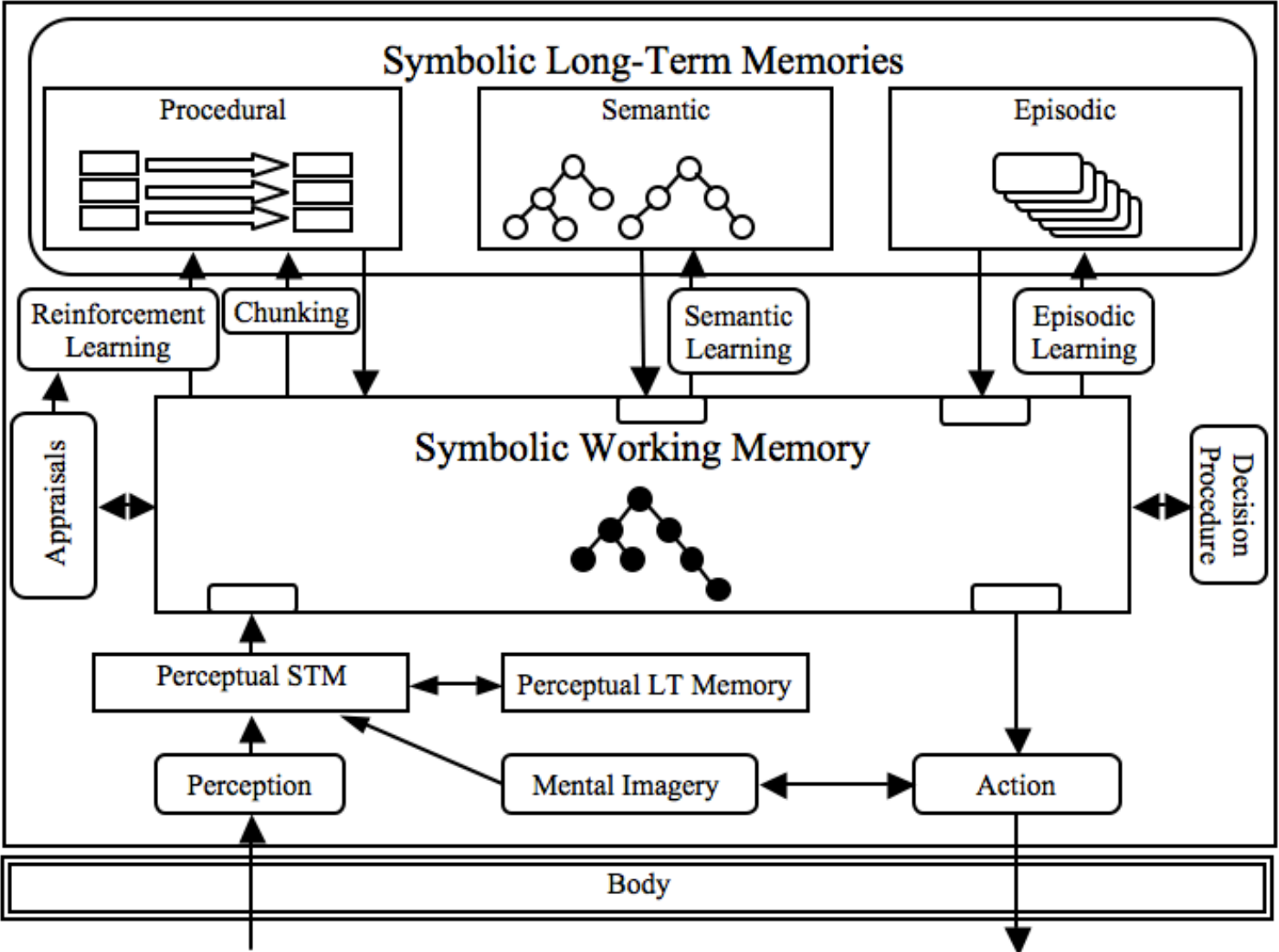


Temporal credit
Assignment problem

Exploration / exploitation
tradeoff

Curse of dimensionality

Soar 9.3.1



Soar-RL

- Reward

```
<state>  
  ^reward-link  
    ^reward  
      ^value float
```

- Value representation

```
sp {rl*move*left  
  (state <s> ^name left-right  
    ^operator <op> +)  
  (<op> ^name move ^dir left)  
-->  
  (<s> ^operator <op> = -1.0) }
```

- Decisions

```
Move*left   -0.8  
Move*right  -0.2  
Move*sit    -1.2
```

- Adaptive behavior

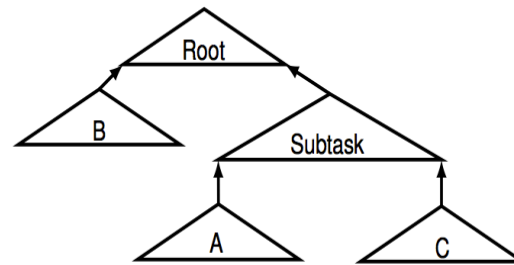


Soar-RL Talks

- Modular RL in Soar
Shiwali Mohan



- Improving Off-Policy HRL
Mitchell Keith Bloch



- Learning to Use Memory
Nick Gorski

