NBDI: A Simple and Effective Termination Condition for Skill Extraction from Task-Agnostic Demonstrations

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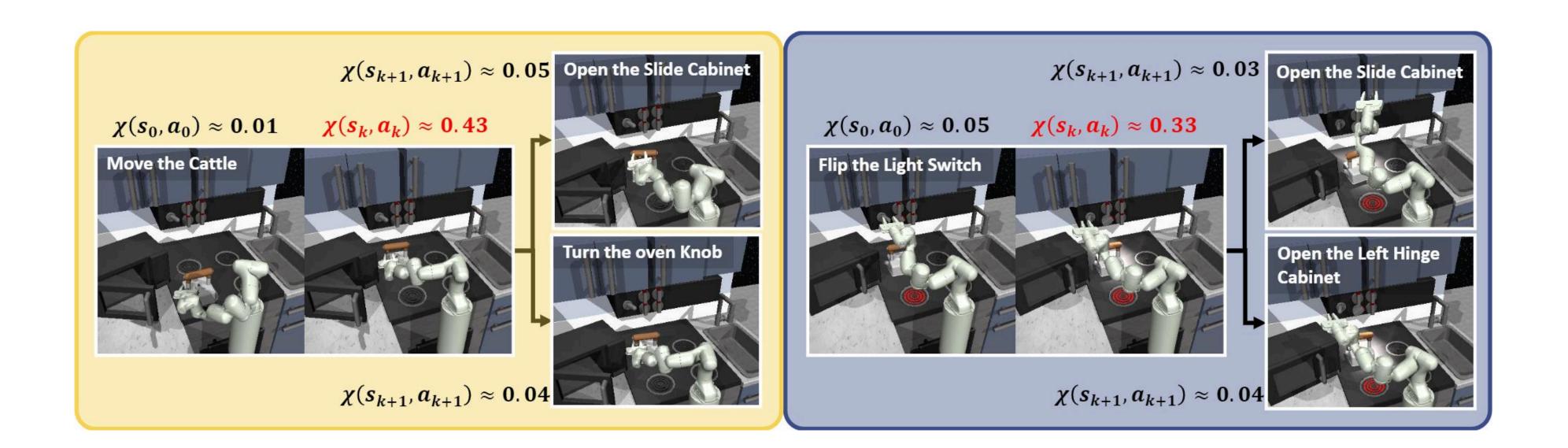






Motivation

- Recently, notable progress has been made in skill-based deep RL models, showing promising results in complex environments and robot manipula tions
- However, the use of fixed-length skills and the absence of appropriate termination conditions often restrict them from making decisions at critical decision points (e.g., crossroads), which can result in significant loss in performance



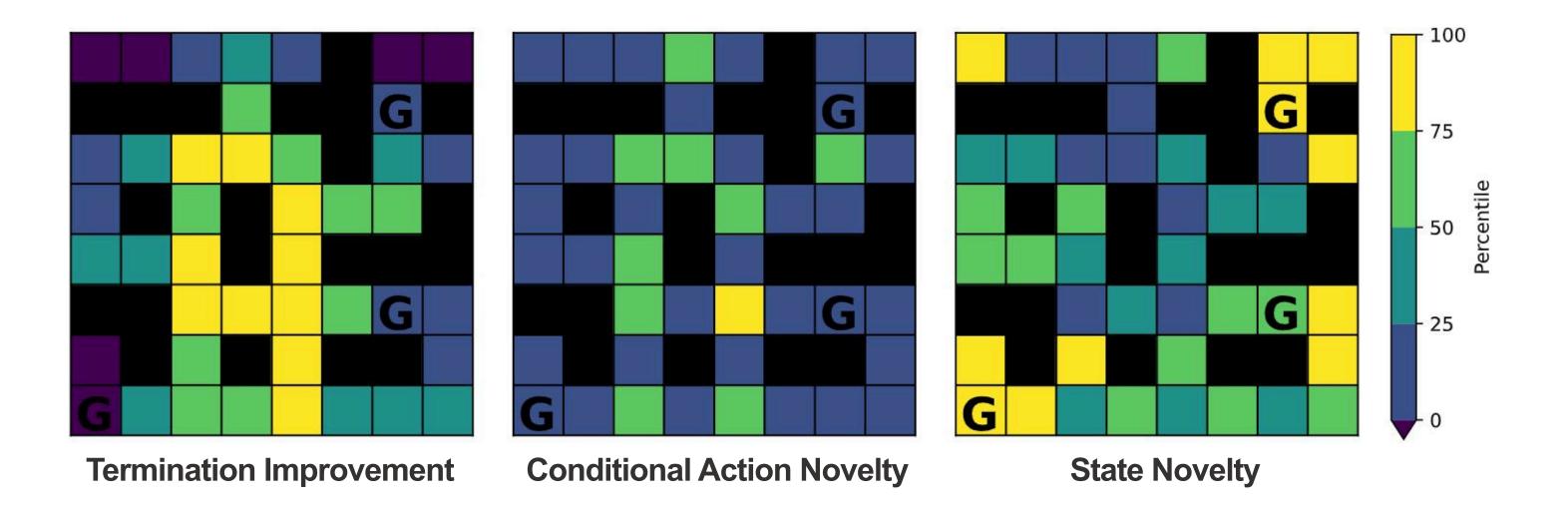






Introduction

- While maximizing skill length is advantageous in terms of temporal abstraction, extended skills can result in suboptimal behavior, especially when the skills are derived from task-agnostic trajectories.
- Such suboptimality of extended skills (or options) can be theoretically quantified using the termination improvement theorem (Sutton, 1998).





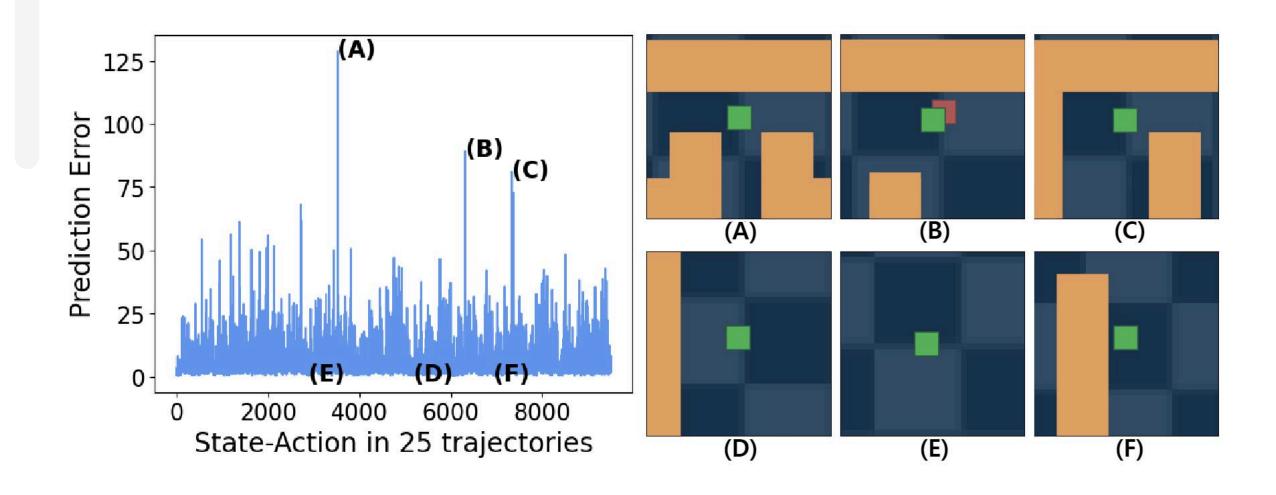


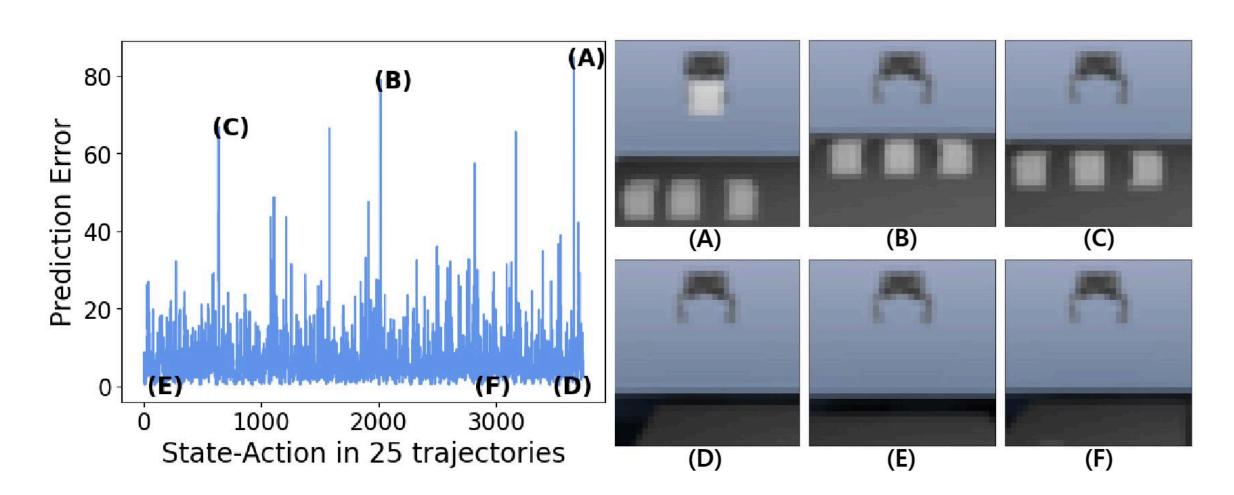


Method

In this work, we propose to use state-action novelty to identify critical decision points for skill termination, which leads to the execution of variable-length skills.

In particular, we use intrinsic curiosity module (ICM) (Pathak et al., 2017) as our state-action novelty estimator



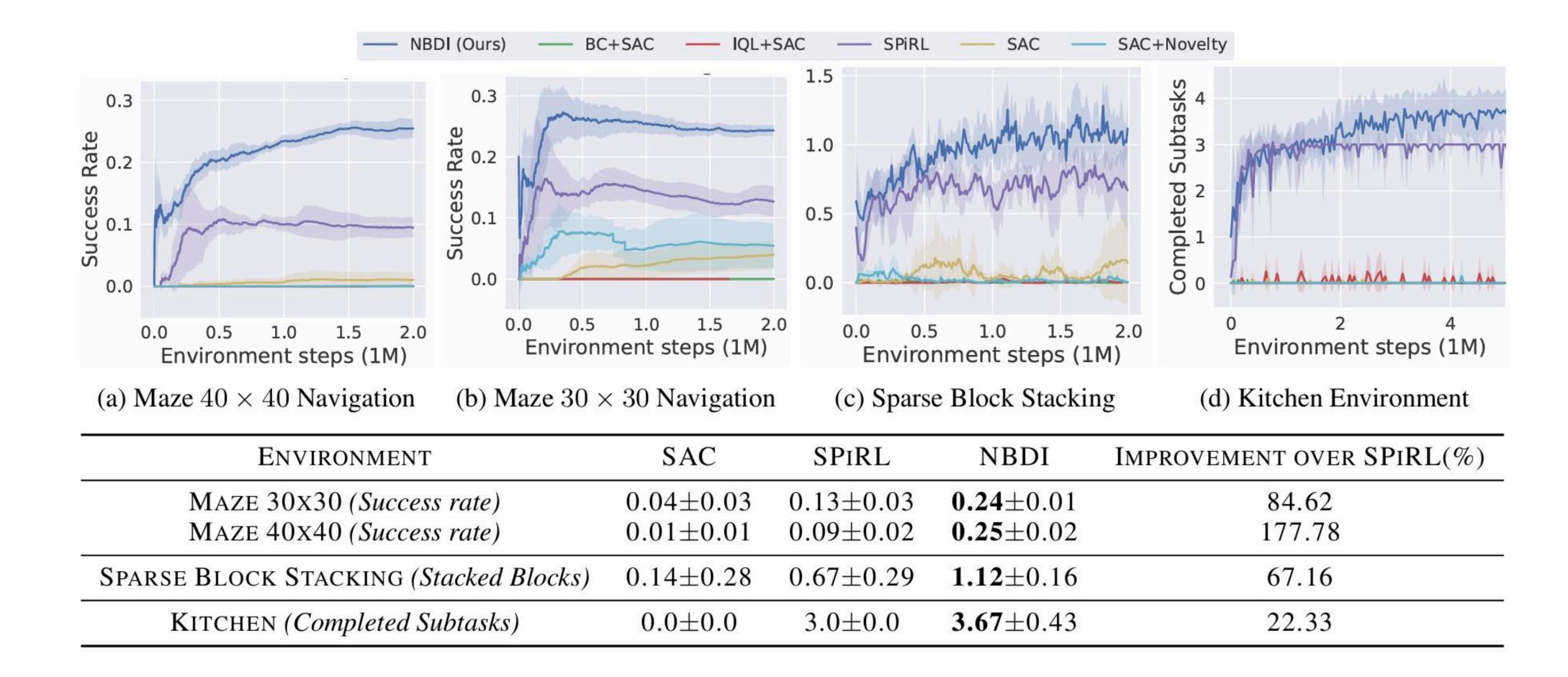








Experiments

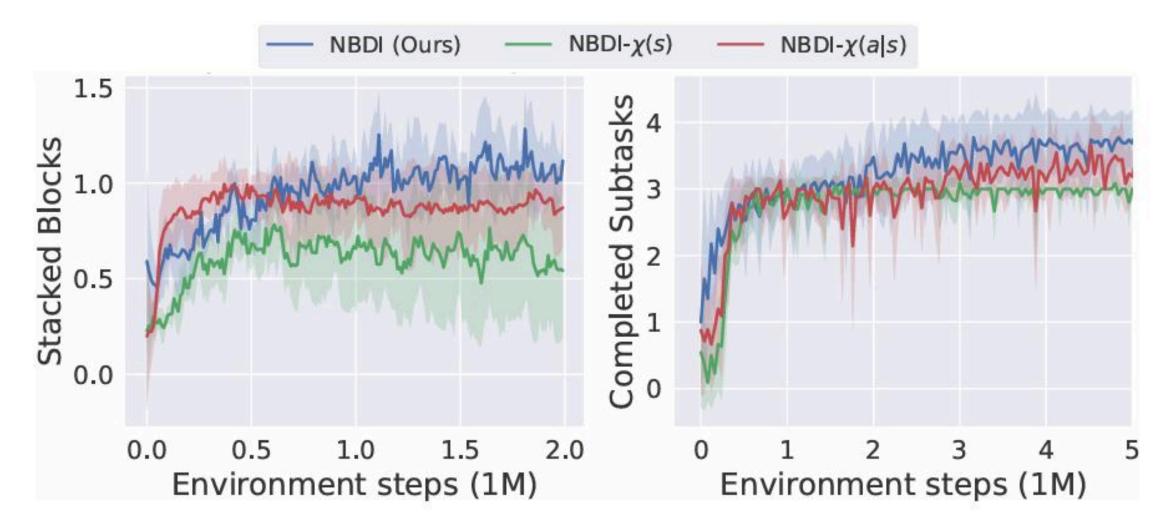




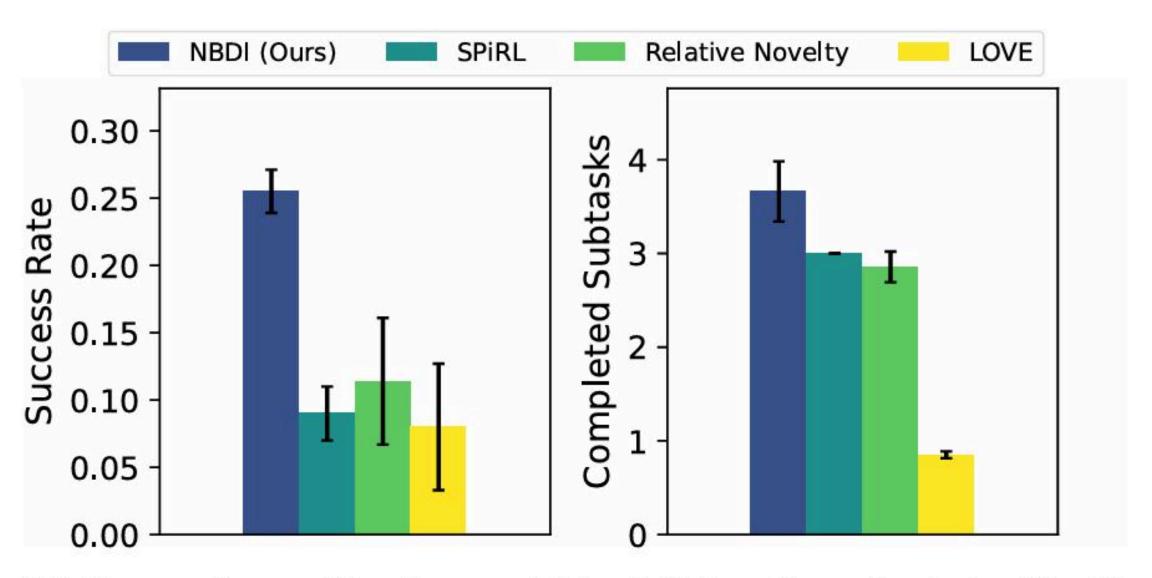




Experiments



(a) Comparison with other terminating criteria in sparse block stacking (left) and kitchen (right) environments



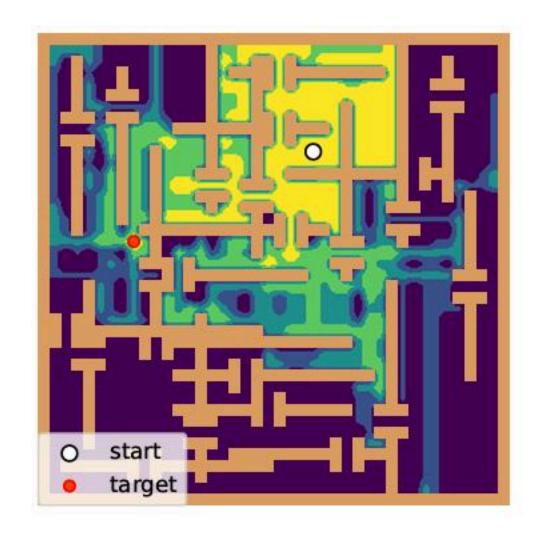
(b) Comparison with other variable skill length methods in 40×40 maze (left) and kitchen (right) environments



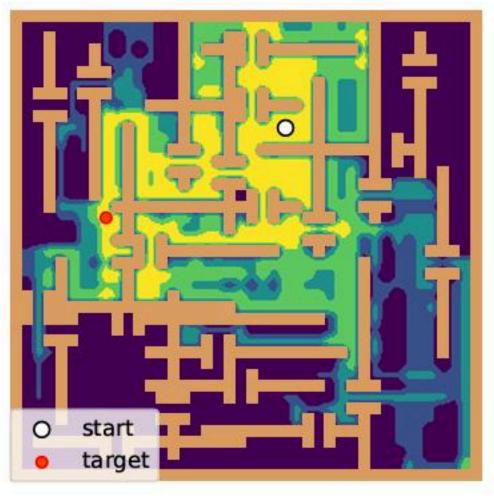




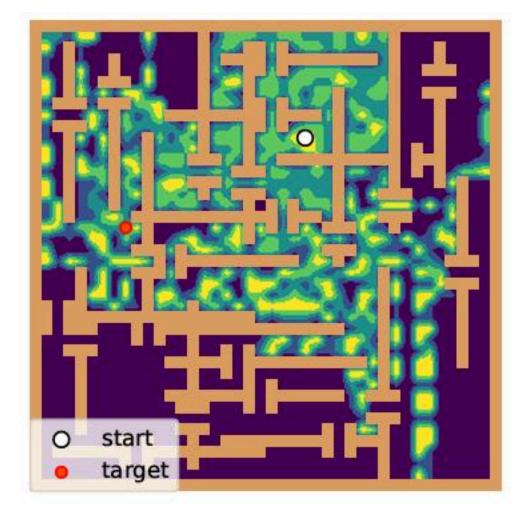
Experiments



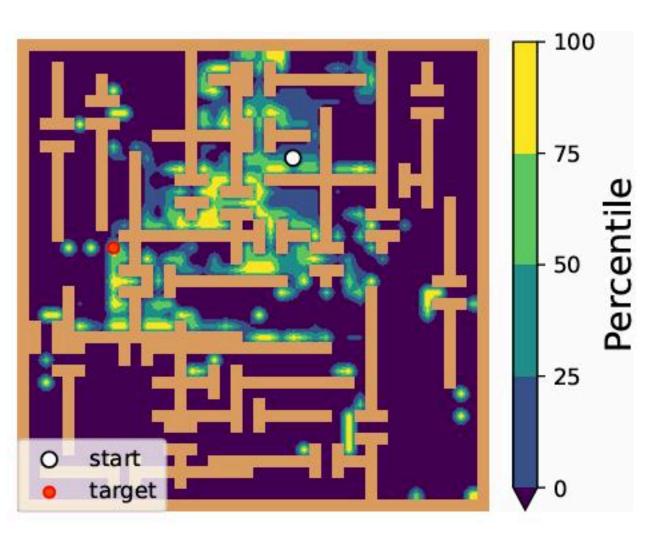
(a) Visitation(SPiRL)



(b) Visitation(NBDI)



(c) Skill Terminat.(SPiRL)



(d) Skill Terminat.(NBDI)





Thankyou