

Belief-Aware Decision Transformers for Offline-to-Online Decision-Making under Partial Observability: A Geosteering Case Study

Hibat Errahmen Djecta^{1,2}, Sergey Alyaev¹, Kristian Fossum¹, and Reidar B. Bratvold²

1. NORCE Research AS, Nygårdsgaten 112, 5008 Bergen, Norway
2. University of Stavanger, Kjell Arholms gate 41, 4021 Stavanger, Norway

Accepted as Spotlight at : ICML 2026 Workshop on Decision-Making from Offline Datasets to Online Adaptation: Black-Box Optimization to Reinforcement Learning, Seoul, South Korea

1 Introduction

Many decisions must be made from noisy, indirect observations of a hidden state. Decision Transformers (DTs) learn offline policies from trajectories, but keep their hidden state implicit — hard to inspect, calibrate, or adapt online. Classical filters give interpretable beliefs, but estimate them separately from the decision, creating a mismatch between what is estimated and what is useful.

Key challenges:

- Hidden state implicit inside the sequence model
- Belief estimation decoupled from decision quality
- Cautious offline-to-online adaptation needed

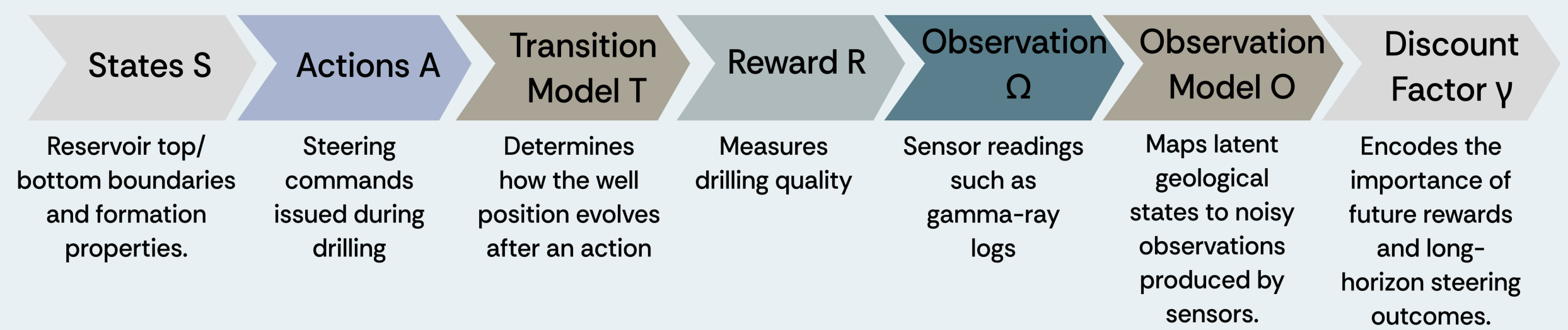
Our idea:

Make hidden state explicit inside a single offline DT — a structured belief head feeding an action head, trained jointly.

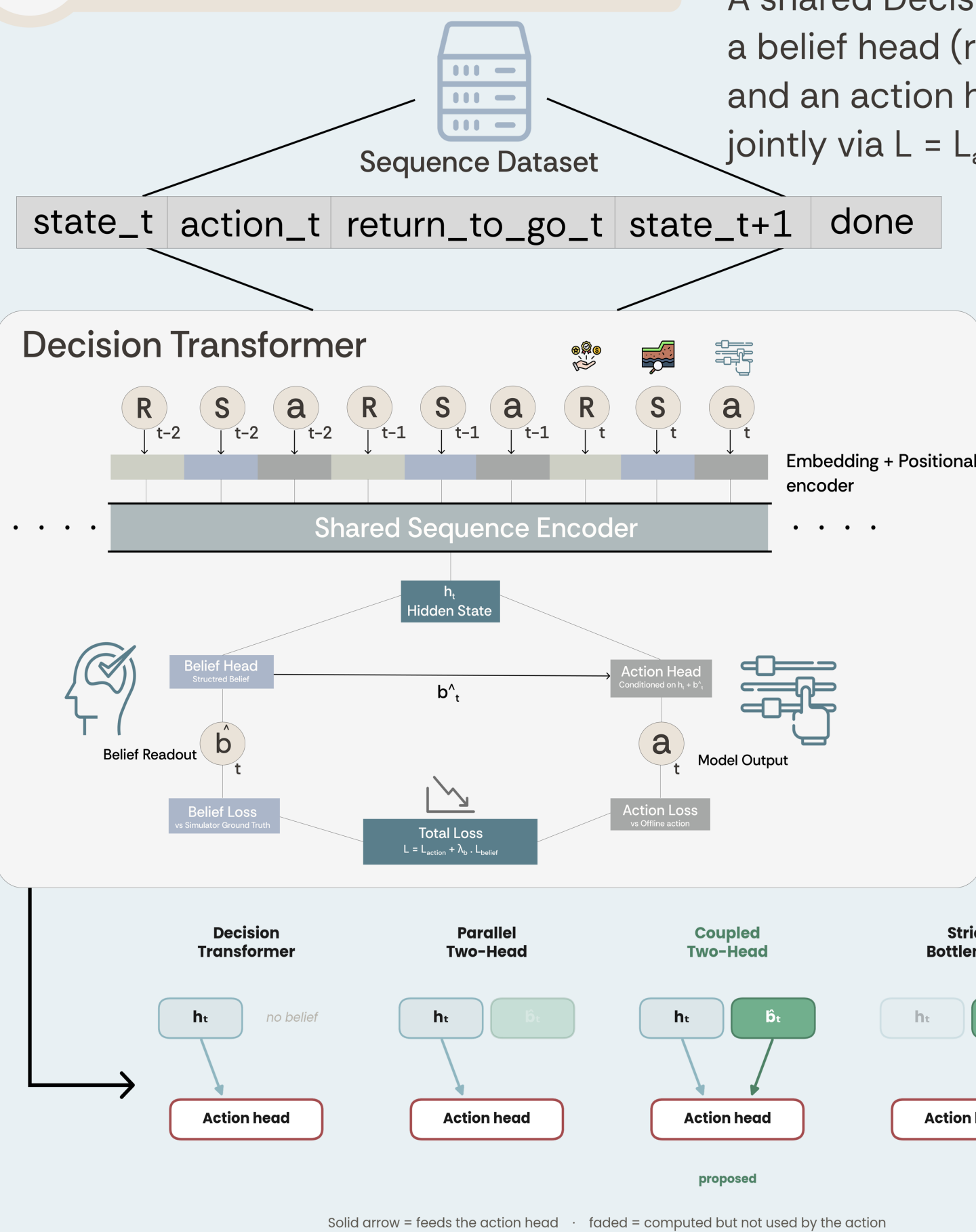
2 Formulation

In geosteering, the agent operates with uncertain and partially observed geological information, receiving noisy sensor signals while its decisions influence future measurements and well placement. This interaction naturally fits a Partially Observable Markov Decision Process (POMDP), which captures both hidden subsurface states and their evolution under action. This structure is consistent with embodied world models, where an agent must infer latent dynamics and act based on how its decisions shape future observations.

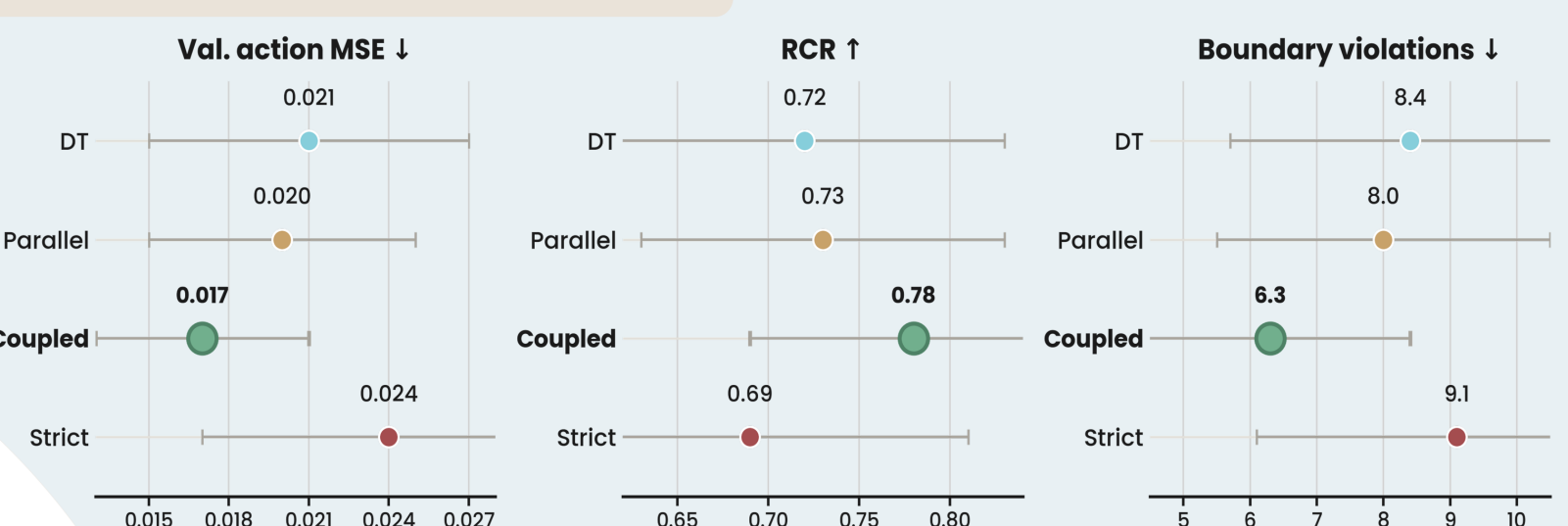
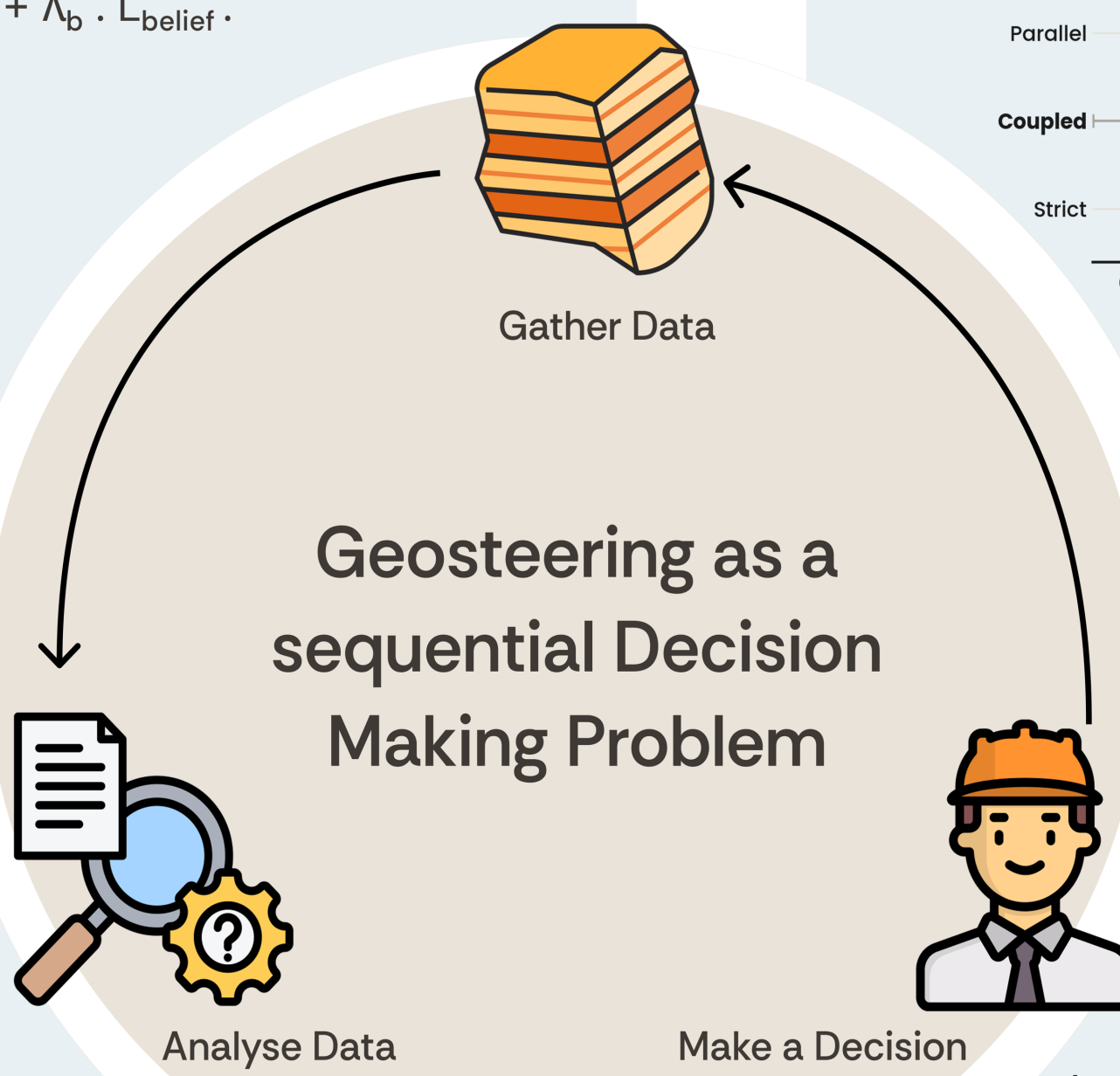
$$\mathcal{P} = (S, A, T, R, \Omega, O, \gamma)$$



3 Approach



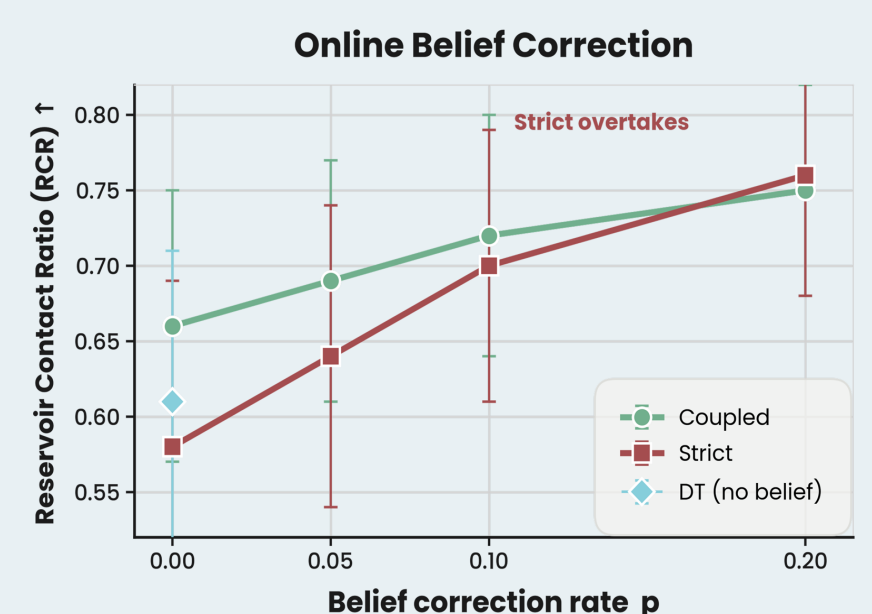
4 Results



Conditioning the action on the predicted belief (Coupled) gives the best decisions, with the highest Reservoir Contact Ratio (RCR) and the fewest boundary violations. Simply adding the belief as an auxiliary task (Parallel) barely improves on the plain DT.

On a shifted test set (gamma-ray noise doubled), correcting only the belief at deployment restores decision quality without retraining. Coupled leads

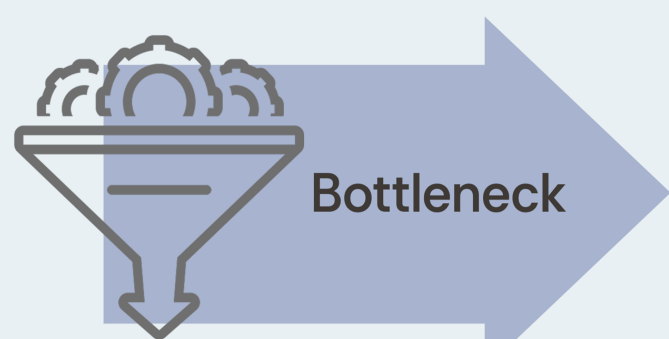
offline, but Strict overtakes as more beliefs are corrected, since its action depends entirely on the belief, so corrections translate directly into better steering.



5 Discussion

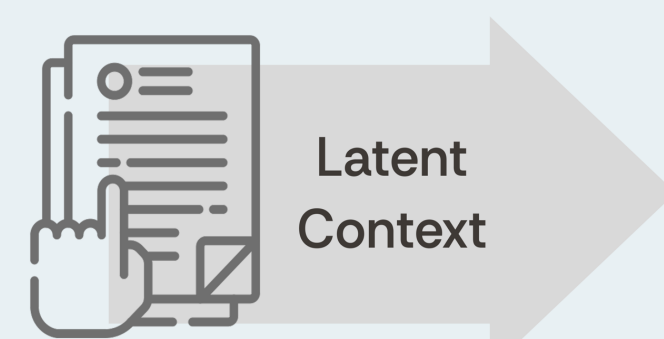
Belief coupling is the main driver of decision quality. The Parallel model, where belief is only auxiliary, performs similarly to the baseline, while the Coupled model achieves the best RCR and fewest violations by using belief directly in the action pathway. The Strict model improves belief accuracy but loses offline decision quality because the compact belief cannot fully replace the richer hidden representation.

Key Insights



Bottleneck improves calibration but reduces control quality:

The Strict model predicts belief more accurately, but relying only on the compact belief removes useful information from the richer hidden state, reducing offline performance.



Offline and online settings favor different designs:

Coupled performs best offline because it uses both structured belief and latent context, while Strict benefits more from online belief correction because belief updates directly affect the actions.

6 Conclusion

A belief-aware Decision Transformer makes hidden, decision-relevant state explicit within an offline sequence model, keeping it interpretable and physically grounded.

Key takeaways:

- Structured beliefs should inform but not entirely constrain offline policies
- Coupled two-head = best balance of interpretability + decision quality
- Physically meaningful belief = a natural interface for offline-to-online adaptation without retraining

References

- Chen, L., Lu, K., Rajeswaran, A., Lee, K., Grover, A., Laskin, M., Abbeel, P., Srinivas, A., Mordatch, I. Decision transformer: Reinforcement learning via sequence modeling. *Advances in Neural Information Processing Systems*, 34, 15084–15097 (2021).
- Djecta, H. E., Alyaev, S., Fossum, K., Bratvold, R. B., Muhammad, R. B., Srivastava, A. Uncertainty-aware well placement: Simulator-verified dual-network reinforcement learning approach meets particle filters. In *Computational Science – ICCS 2025 Workshops*, pp. 188–202. Springer Nature Switzerland (2025a).
- Djecta, H. E., Alyaev, S., Fossum, K., Bratvold, R. B., Sui, D. Geosteering through the lens of decision transformers: Toward embodied sequence decision-making. *NeurIPS 2025 Workshop on Embodied World Models for Decision Making* (2025b).
- Gangwani, T., Lehman, J., Liu, Q., Peng, J. Learning belief representations for imitation learning in POMDPs. *arXiv:1906.09510* (2019).
- Kaelbling, L. P., Littman, M. L., Cassandra, A. R. Planning and acting in partially observable stochastic domains. *Artificial Intelligence*, 101(0), 99–134 (1998).
- Kullawar, K., Bratvold, R., Bickel, J. E. A decision analytic approach to geosteering operations. *SPE Drilling & Completion*, (2014).
- Muhammad, R. B., Srivastava, A., Alyaev, S., Bratvold, R. B., Tartakovsky, D. M. High-precision geosteering via reinforcement learning and particle filters. *Computational Geosciences*, (2025).
- Muhammad, R. B., Alyaev, S., Bratvold, R. B. Optimal sequential decision-making in geosteering: A reinforcement learning approach. *Geoenery Science and Engineering*, 258, 214304 (2026).



Available On
your phone