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Darken, Christian J.

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# Towards Learned Anticipation in Complex Stochastic Environments

**Christian J. Darken**

Department of Computer Science  
Naval Postgraduate School  
Monterey, CA 93943

## Abstract

We describe a novel methodology by which a software agent can learn to predict future events in complex stochastic environments. It is particularly relevant to environments that are constructed specifically so as to be able to support high-performance software agents, such as video games. We present results gathered from a first prototype of our approach. The technique presented may have applications that range beyond improving agent performance, in particular to user modeling in the service of automated game testing.

## Introduction

One of the challenges on the long term agenda of AI for interactive entertainment is producing software agents that are proactive, i.e. that understand their environment to the degree that they are able to predict what is likely to happen next and can therefore take appropriate measures. Unlike other software agent construction tasks where the information available to the agent via its virtual sensors is fixed in advance, for a computer game the environment and agent are built together, thus opening up the possibility of adjusting the nature of agent perception to improve the system as a whole. In contexts where agent perception can be adjusted to suit, we propose that very simple, transparent learning schemes may be a practical approach to allow an agent to predict the likely course of events in its environment.

In order to explore our hypothesis, we have created a simple game in the RPG (role-playing game) family. We then implemented a sensory interface that passes percepts coded in a first-order logic subset to the agent. The agent then attempts to predict the next percept that it will see. This environment is both stochastic and complex. "Stochastic" implies that future percepts are not a function of the sequence of previous ones. This environment may be considered complex in many senses, beginning with the fact that, although it is a small and simple game as such games go, its state space is very large. More significant, we believe, is the fact that there is no obvious way for the agent to sum up its information about the world in a representation of fixed dimension, i.e. that some aspects of first-order logic are apparently needed in order to accomplish the task. Our impression is

that learning algorithms that can succeed in stochastic domains without obvious representations of fixed dimension are of interest for many domains stretching far beyond interactive entertainment applications.

## Related Work

Anticipation of hostile unit behavior in the context of computer games has previously been addressed in (Laird 2001), who had the agent apply its own action selection procedure based on the information probably possessed by the hostile unit in order to guess what the hostile would do. In this work, we are attempting to learn to anticipate without hand-coded rules. Further, while hostile unit behavior is one of the things we would like to predict, it is not the only thing.

We have not been successful in finding known algorithms that we can productively compare with our approach. Logical rules, including some types of predictive rules, can be learned by algorithms such as FOIL (Mitchell 1997). However, these algorithms assume a deterministic domain. Hidden Markov Models (R. Duda & Stork 2001) are well suited to stochastic domains, but assume a finite state space, and in practice state spaces that are finite but large are problematic.

## Benchmark Environment

Our benchmark environment is a simple virtual environment with a text interface modeled after the DikuMUD family of combat oriented MUD's. This family of games is instantly comprehensible to a player of World of Warcraft or Everquest 2, to name two current exemplars, and is arguably a progenitor of these systems. Players of this type of game assume the role of a young adventurer. The goal of the game is to expand the power of one's in-game avatar to the maximum extent possible. This goal is primarily accomplished by slaying the monsters that roam the virtual environment. Slaying monsters results in improvements to the avatar's capabilities through an abstracted model of learning ("experience points") and also through the items ("loot") that the slain monsters drop or guard, which either consist of or may be traded for more powerful combat gear.

The benchmark environment consists of 19 locations, four monsters of three different types, and four different weapon types, of which there may be any number of instantiations. Growth of combat capabilities through experience has not

```
Paperville
Terrified eyes peer from every window
  of this besieged hamlet.
Contents: pitchfork, wand, Conan
```

```
get pitchfork
```

```
You get the pitchfork.
```

```
equip pitchfork
```

```
You equip the pitchfork.
```

```
w
```

```
The Eastern Meadow
All the grass has been trampled into
  the dirt, and tiny footprints are
  everywhere.
Contents: Conan
```

Figure 1: The beginning of a session with the benchmark environment as it appears to a human player named Conan.

been modeled, therefore, improved capability comes only by acquiring more powerful weapons. The environment as a whole may be conceived of as a discrete event system with a state that consists of the Cartesian product of some number of variables. The system remains in a state indefinitely until an event is received, at which time it may transition to a new state.

The benchmark environment together with networking and multiplayer infrastructure was coded from scratch in Python. The system uses a LambdaMOO-like method dispatch mechanism to determine which game object should process a player action. An unusual feature is the ability to provide output in English text and/or in a first-order logic fragment, as shown in Figures 1 and 2.

### Perceptual Model

We have implemented text-based interfaces to allow both humans and software agents to interact with the benchmark environment. The human interface consists of English text. We describe the agent interface below.

Perception for software agents in the benchmark environment is modeled as direct access to a subset state variables and system events. The subset of visible events and variables depends upon the location of the agent in the environment, i.e. an agent receives information only about occurrences in his immediate location. The agent's own actions also generate percepts. Thus, four types of percepts are required. 'A' represents agent actions. 'E' represents events. '+' represents the beginning of a time interval in which a variable was sensed to have a particular value. When the variable changes value, or it can no longer be sensed, a '-' percept is received. We form logical atoms from percepts whenever needed by appending the percept type to the percept name to create a predicate (i.e. a percept of type 'E' with name

```
(A 40.6979999542 look)
(+ 40.7079999447 location pitchfork
  Paperville)
(+ 40.7079999447 location wand
  Paperville)
(+ 40.7079999447 location Conan
  Paperville)

get pitchfork

(A 44.6440000534 get pitchfork)
(E 44.6440000534 get Conan pitchfork)
(- 44.6440000534 location pitchfork
  Paperville)
(+ 44.6440000534 location pitchfork
  Conan)

equip pitchfork

(A 47.6080000401 equip pitchfork)
(+ 47.6080000401 equipping Conan
  pitchfork)

w

(A 51.2130000591 w)
(E 51.2130000591 go Conan west)
(- 51.2130000591 location wand
  Paperville)
(- 51.2130000591 location Conan
  Paperville)
(+ 51.2130000591 location Conan
  The_Eastern_Meadow)
```

Figure 2: The beginning of the same session described in Figure 1 with the benchmark environment as it would appear to a software agent named Conan. The first four percept fields are: type, time stamp, percept name. These are followed by the percept arguments, if any.



```

{[loc+ Ed road]      |
 [loc+ Fox2 road]   |
 [goE Fox2 east]}  1 | (loc- Fox2 road) 1

```

would be added to the table.

### Patterns with Variables

The exact matching technique makes predictions that are specific to specific objects in the environment. In environments where an object may be encountered only once and never again, for example, this is not very useful. By replacing references to specific objects by variables, we produce a technique that generalizes across objects. In this technique, left column entries contain variables instead of constants. A new situation matches the entry if there is a one-to-one substitution of the variables to constants in the situation. A one-to-one substitution is a list of bindings for the variables, that has the property that one and only one variable can be bound to one specific constant. The reason for the constraint to one-to-one substitutions is to ensure that each situation matches at most one pattern (left column entry). This restriction is not necessary, but it is convenient. Right column entries can also contain variables in this model. Given a match of a pattern to a situation, the predicted percept distribution is given by applying the substitution to the atoms in the right column distribution. Note that it may be the case that some variables remain in the prediction even after the substitution is applied.

As each percept arrives, it is used to train the predictor function as follows. The situation is generated and matched against all entries in the left-hand column of the table. It can match at most one. If a match is found, the substitution (list of variable-to-constant bindings) is kept, and the counter for the entry is incremented. Then the substitution is applied to each element of the predicted percept distribution, and the percept is matched against it. If it matches, the counter for that element is incremented. If it fails to match any element of the distribution, it is “variablized” by replacing each constant with the corresponding variable from the substitution, and replacing each remaining constant with a new variable, and then added as a new element of the distribution with a new counter initialized to one. If the situation matches no left-hand column entry, a new entry is added, consisting of the situation with each constant replaced by a variable.

### Experimental Results

We created a software agent that takes random actions (one every 0.25 seconds) and connected it to the benchmark environment. Since the action generator is not very intelligent, many actions elicit what are essentially error messages from the environment. We do not consider this a problem. In fact, we would like the agent to learn when an action will be fruitless.

We describe the results of a typical run. For this run, percepts were defined as relevant if they had been received in the last 0.1 seconds or if they were in the agent’s current sensation. The agent was allowed to explore the environment for about one and one quarter hours of real time while the

learning algorithm ran concurrently. 38519 percepts were received and processed during the run.

The exact matching approach produced 5695 predictors (rows in the table). The approach with variables produced only 952, much fewer, as might be expected.

Numeric results are given in Figures 3 and 4. The average predicted probability of the percepts as a function of time is presented in Figure 7. Note that by the end of the run, both curves are fairly flat. The exact match curve is lower, but increasing faster.

For the approach with variables, the prediction is considered correct if it matches the actual next percept (to within a one-to-one variable substitution). Note that the agent’s own actions, being randomly generated, were the most difficult to predict. Neglecting type ‘A’ percepts, the average predicted probability of all remaining percepts is 66.6 percent for the exact match model and 70.5 percent for the model with variables. This strikes us as reasonably high given the fine-grained nature of the predictions, the simplicity of the algorithm and the high degree of remaining irreducible randomness in the environment caused by random movements of monsters and outcomes of each attempted strike in combat. A significant number of mistakes seemed to be caused by forgetting of important percepts caused by the severe recency threshold used (0.1 sec). We have found that the simple table-based predictive model does not scale well to the recency threshold of multiple seconds that would be seem to be necessary to solve the problem without modifying the agents perception to be more informative.

Detailed analysis of the top five types of errors for each algorithm shows that both algorithms are strongly impacted by the 0.1 sec recency threshold. The worst symptom is that the algorithms are unable to predict combat-related messages accurately because they can not tell that they are in combat. They can not tell that they are in combat because there is nothing in the sensation that indicates ongoing combat, and combat rounds are spaced at intervals of about two seconds.

For the exact matching algorithm, the most common errors stem from the simple fact that, being completely unable to generalize, many situations look completely novel, even at the end of the run. This difference can be clearly seen in the histograms of the last 5000 prediction probabilities presented as Figures 5 and 6. The exact match algorithm has more predictions with probability one than the variable-based algorithm, but it also has more with probability zero, indicating the absence of a match with any table entry.

The variable-based approach scored better than the exact matching algorithm overall. Nonetheless, the lack of predicates for indicating object type in the benchmark environment caused an interesting problem for this approach. For example, this approach was unable to predict the results of attempts to ‘get X’, and therefore had to hedge its bets between success and an error message. This was no issue for the exact match algorithm, as it could learn that ‘get Troll’ would provoke an error while ‘get sword’ would succeed. Note that the addition of a ‘portable’ predicate, for example, would mitigate this problem.

Type	Avg. Probability	Occurrences	Error
A	7.65%	14488	65.5%
E	72.09%	14905	20.3%
+	45.92%	4563	12.1%
-	69.28%	4563	6.9%

Figure 3: Performance summary for exact matching. The average predicated probability over all percepts was 44.43%. Error is the expected fraction of the total number of prediction errors for percepts of the given type.

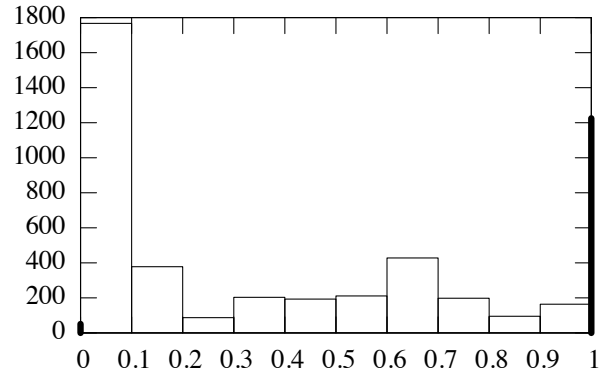


Figure 6: Prediction probability for the last 5000 percepts of the run with variables. The black bars represent the predictions of exactly 0 or 1.

Type	Avg. Probability	Occurrences	Error
A	7.82%	14488	65.3%
E	66.39%	14905	24.5%
+	65.12%	4563	7.8%
-	89.32%	4563	2.4%

Figure 4: Performance summary for patterns with variables. The average predicted probability over all percepts was 46.94%. Error is the expected fraction of the total number of prediction errors for percepts of the given type.

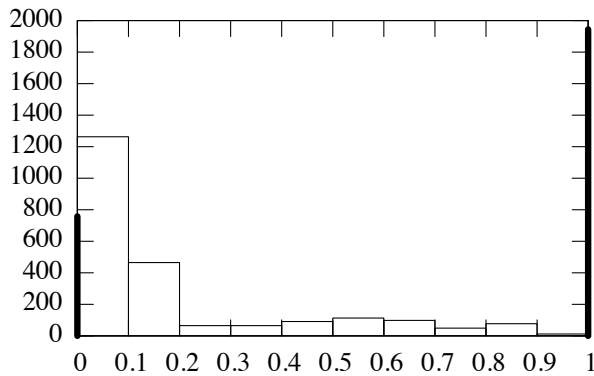


Figure 5: Prediction probability for the last 5000 percepts of the run with constants. The black bars represent the predictions of exactly 0 or 1.

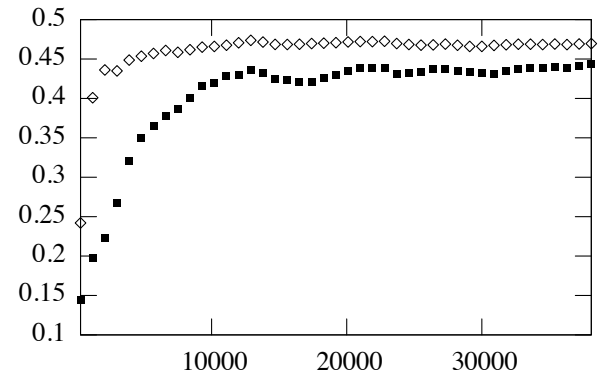


Figure 7: Average prediction probability as a function of the number of percepts received. White diamonds represent the algorithm with variables and black squares the algorithm with constants.

## Discussion

A few comments on the structural characteristics of the methods presented in this paper are in order.

One very positive characteristic of these techniques is that there is a clear “audit trail” that can be followed when the agent makes unexpected predictions. I.e. each row in the table can be traced to a specific set of prior experiences that are related to the predictions it makes in an obvious way. Many machine learning techniques do not share this characteristic.

One can conceive of interesting schemes that are combinations of the two presented techniques. For example, one might try to predict the next percept with an exact matching model first, but if no prediction was available (or if the prediction was based on too little data), one might revert to a simultaneously developed variable-based predictor. Alternatively, one might design the environment so that percept references to objects were either existentially quantified variables or constants. A hybrid model could be developed which would then produce patterns with variables or constants based on what was present in the percept. This places the burden of deciding how the predictor should behave onto the percept designer.

Note that the situations in the left column of the table divide all possible percept sequences into a set of equivalence classes, i.e. many percept sequences can map into a single situation set. To the agent, only membership in the sequence sets specified in the left column of the table matter. It will never be able to discriminate between different percept sequences that map into the same sequence set. The temptation naturally arises to make these sets as differentiated as possible by, for example, increasing the recency threshold or using exact matching instead of patterns with variables. Likewise, one could adapt the methods we present to be sensitive to percept order. But increasing the fineness of the situation sets is a two-edged sword. While it does indeed make it possible for the agent to discriminate between different percept sequences that it could not differentiate before, it also makes it increasingly rare that the agent visits situations that it knows about. Figures 5, 6, and 7 illustrate this fact.

## Future Work

Although we have not discussed it previously, note that it is possible to extend the system as described to making predictions about *when* the next percept will be received in addition to what the next percept will be along the lines described in (Kunde & Darken 2005).

Two key directions for further investigation are improved predictive models and systematic exploitation of the predictions. The technique described in this work is very limited in its generalization capabilities. Unlike FOIL, which searches through candidate atoms and includes only the most promising in the model, the current approach takes all atoms that have passed the relevance test. It would be nice to have an approach that could perhaps learn from experience which of the relevant atoms were actually necessary to accurate prediction.

While we take for granted that many special-purpose schemes can be constructed which can improve agent behav-

ior based on the ability to predict future percepts, it seems worth pointing out that one can search over the space of potential courses of action using the predictive model and a quality function to decide which course to adopt. This is a homogeneous and general-purpose method of exploiting prediction very similar in spirit to the model predictive control techniques that are an established part of chemical engineering (Morari & Lee 1997). It has been explored within the computer science literature as well (Sutton & Barto 1981).

Finally, we believe that the predictive model may have potential for improving the automated testing of computer games. It is already the case that automated “button mashing”, i.e. random control inputs, are used to test the stability of computer and video games. The model described could be applied to capture, if crudely, typical user behavior as a function of game state. The model could then be simulated Monte Carlo style to generate large numbers of random tests that are more focused on the types of behavior that users actually have.

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