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function [Q,ets,numFinishes,Model_ns,Model_nr,cr] =
dynaQ_maze(alpha,epsilon,gamma,nPlanningSteps,mz_fn,s_start,s_end,MAX_N_STEPS)
% DYNAQ_MAZE - Runs the dynaQ planning algorithm on a "maze" mz_fn
%
% Input:
%   gamma: the discount factor
%   epsilon: our epsilon greedy policy
%
% Ones correspond to locations we can be.
%
% Written by:
% --
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%
% email: wax@alum.mit.edu
%
% Please send comments and especially bug reports to the
% above email address.
%
%-----

PLOT_STEPS = 0;

% get the initial maze dimensions:
MZ = mz_fn(0);
[sideII,sideJJ] = size(MZ);

% the maximal number of states:
nStates = sideII*sideJJ;

% on each grid we can choose from among at most this many actions:
nActions = 4;

% An array to hold the values of the action-value function ... with planning
% it seems that the RL algorithm is very sensitive to the initial conditions
% we take for Q ... this value seems to work for planning steps 0 ... 50
%Q = mean( [-1,0] )*ones(nStates,nActions);
Q = -3*ones(nStates,nActions);
%Q = zeros(nStates,nActions);

% storage for the sequence of states we have observed
% (these are stored as indices ... as produced by the matlab command "sub2ind.m")
seen_states = [];
% storage for the sequence of actions taken in each state
% (0=>this action was never taken; 1=>action was taken)
act_taken = zeros(nStates,nActions);

% Some arrays to hold the model of the environment (assuming it is deterministic):
Model_ns = zeros(nStates,nActions); % <- next state we will obtain
Model_nr = zeros(nStates,nActions); % <- next reward we will obtain

if( PLOT_STEPS )
    figure; imagesc( zeros(sideII,sideJJ) ); colorbar; hold on;
    plot( s_start(2), s_start(1), 'x', 'MarkerSize', 10, 'MarkerFaceColor', 'k' );
    plot( s_end(2), s_end(1), 'o', 'MarkerSize', 10, 'MarkerFaceColor', 'k' );
end

% keep track of how many timestep we take per episode:
ets = []; ts=0;

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% keep track of how many times we reach the end of our maze:
numFinishes = 0;

% keep track of how many times we have solved our problem in this number of timesteps:
cr = zeros(1,MAX_N_STEPS+1); cr(1) = 0;

% initialize the starting state
st = s_start; sti = sub2ind( [sideII,sideJJ], st(1), st(2) );
for tsi=1:MAX_N_STEPS,
    tic;
    % if( tsi==1 )
    %     fprintf('working on step %d...\n',tsi);
    % else
    %     fprintf('working on step %d (ptt=%10.6f secs)...\n',tsi, toc); tic;
    % end
    if( 0 && mod(tsi,100)==0 )
        fprintf('working on step %d (ptt=%10.6f secs)...\n',tsi, toc); tic;
    end

    % pick action using an epsilon greedy policy derived from Q:
    [dum,at] = max(Q(sti,:)); % at \in [1,2,3,4]=[up,down,right,left]
    if( rand<epsilon ) % explore ... with a random action
        tmp=randperm(nActions); at=tmp(1);
    end

    % keep track of the states/action seen
    if( ~ismember(sti,seen_states) ) seen_states = [ sti; seen_states ]; end
    act_taken( sti, at ) = 1;

    % propagate to state stp1 and collect a reward rew
    MZ = mz_fn(tsi); % <- get the current maze for this timestep
    [rew,stp1,stpli] = stNac2stp1(st,at,MZ,sideII,sideJJ,s_end);
    %fprintf('stp1=(%d,%d); rew=%3d...\n',stp1(1),stp1(2),rew);

    % update our action-value function:
    if( ~( (stp1(1)==s_end(1)) && (stp1(2)==s_end(2)) ) ) % stp1 is not the terminal state
        Q(sti,at) = Q(sti,at) + alpha*( rew + gamma*max(Q(stpli,:)) - Q(sti,at) );
    else % stp1 IS the terminal state ...
        % no Q(s';a') term in the sarsa update
        Q(sti,at) = Q(sti,at) + alpha*( rew - Q(sti,at) );
    end

    % update our model of the environment:
    Model_ns(sti,at) = stpli;
    Model_nr(sti,at) = rew;

    % perform some planning steps:
    for pi=1:nPlanningSteps,
        %fprintf('planning step = %10d...\n',pi);
        % pick a random state we have seen "r_sti":
        tmp = randperm(length(seen_states)); r_sti = seen_states(tmp(1));

        % pick a random action from the ones that we have seen (in this state) "r_ati":
        pro_action = act_taken(r_sti,:)/sum(act_taken(r_sti,:)); % <- the probability of each
        specific action ...
        r_ati = sample_discrete( pro_action, 1, 1 );

        % get our models prediction of the next state (and reward) "model_sprimei",
        "model_rew":

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    model_sprimei = Model_ns(r_sti,r_ati);
    [ii,jj]       = ind2sub( [sideII,sideJJ], model_sprimei );
    model_sprime(1) = ii; model_sprime(2) = jj;
    model_rew       = Model_nr(r_sti,r_ati);
    %fprintf( 'm_sprimei=%10d, m_sprimt=(%10d,%10d)\n', model_sprimei, model_sprime(1),
model_sprime(2) );

    % update our action-value function:
    if( ~( (model_sprime(1)==s_end(1)) && (model_sprime(2)==s_end(2)) ) ) % model_sprime
is not the terminal state
        Q(r_sti,r_ati) = Q(r_sti,r_ati) + alpha*( model_rew + gamma*max(Q(model_sprimei,:))
- Q(r_sti,r_ati) );
    else % model_sprime IS the terminal
state ... no Q(s';a') term in the sarsa update
        Q(r_sti,r_ati) = Q(r_sti,r_ati) + alpha*( model_rew - Q(model_sprimei,r_ati) );
    end
    %fprintf('Q(r_sti=%5d,r_ati=%5d) = %10.6f\n',r_sti,r_ati,Q(r_sti,r_ati));

    if( PLOT_STEPS && ts>8000 )
        num2act = { 'UP', 'DOWN', 'RIGHT', 'LEFT' };
        plot( st(2), st(1), 'o', 'MarkerFaceColor', 'g' ); title( ['action =
',num2act(atp1)] );
        plot( stp1(2), stp1(1), 'o', 'MarkerFaceColor', 'k' ); drawnow;
    end

    %pause;
end % end planning loop

% shift everything by one (this completes one "step" of the algorithm):
st = stp1; sti = stpli; ts=ts+1;

% for continual planning ... if we have "solved" our maze we will start over:
if( ( (stp1(1)==s_end(1)) && (stp1(2)==s_end(2)) ) ) % stp1 is the terminal state
    st = s_start; sti = sub2ind( [sideII,sideJJ], st(1), st(2) );
    % record that we took "ts" timesteps to get to the solution (end state)
    ets = [ets; ts]; ts=0;
    % record that we got to the end:
    numFinishes = numFinishes+1;
    % record that we got to the end:
    cr(tsi+1) = cr(tsi)+1;
else
    % record that we did not get to the end and our cummulative reward count does not
change:
    cr(tsi+1) = cr(tsi);
end

end % end episode loop

function [rew,stp1,stpli] = stNac2stp1(st,act,MZ,sideII,sideJJ,s_end)
% STNAC2STP1 - state and action to state plus one and reward
%

% convert to row/column notation:
ii = st(1); jj = st(2);

% incorporate any actions and fix our position if we end up outside the grid:
%
switch act
case 1,

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%
% action = UP
%
stp1 = [ii-1,jj];
case 2,
%
% action = DOWN
%
stp1 = [ii+1,jj];
case 3,
%
% action = RIGHT
%
stp1 = [ii,jj+1];
case 4
%
% action = LEFT
%
stp1 = [ii,jj-1];
otherwise
    error(sprintf('unknown value for of action = %d',act));
end

% adjust our position of we have fallen outside of the grid:
%
if( stp1(1)<1      ) stp1(1)=1;      end
if( stp1(1)>sideII ) stp1(1)=sideII; end
if( stp1(2)<1      ) stp1(2)=1;      end
if( stp1(2)>sideJJ ) stp1(2)=sideJJ; end

% if this transition has placed us at a forbidden place in our maze no transition takes
place:
if( MZ(stp1(1),stp1(2))==1 )
    stp1 = st;
end

% convert to an index:
stp1i = sub2ind( [sideII,sideJJ], stp1(1), stp1(2) );

% get the reward for this step:
%
if( (ii==s_end(1)) && (jj==s_end(2)) )
    rew=0;
    %rew = 1;
else
    rew=-1;
    %rew = 0;
end

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