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function [Q,ets] = windy_gw(alpha,sideII,sideJJ,s_start,s_end,wind,MAX_N_EPISODES)
% WINDY_GR - Performs on-policy sarsa iterative action value funtion estimation
% for the windy grid world example.
%
% Written by:
% --
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%
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%
% Please send comments and especially bug reports to the
% above email address.
%
%-----

PLOT_STEPS = 0;

gamma = 1;    % <- take this is an undiscounted task

epsilon = 0.1; % for our epsilon greedy policy

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

% on each grid we can choose from among this many actions (except on edges where this
action is reduced):
nActions = 4;

% An array to hold the values of the action-value function
Q = zeros(nStates,nActions);

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 = zeros(MAX_N_EPISODES,1); ts=0;
for ei=1:MAX_N_EPISODES,
    tic;
    if( ei==1 )
        fprintf('working on episode %d...\n',ei);
    else
        fprintf('working on episode %d (ptt=%10.6f secs)...\n',ei, toc); tic;
    end
    ets(ei,1) = ts+1;
    % initialize the starting state
    st = s_start; sti = sub2ind( [sideII,sideJJ], st(1), st(2) );

    % 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

    % begin the episode
    while( 1 )
        ts=ts+1;

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%fprintf('st=(%d,%d); act=%3d...\n',st(1),st(2),at);
% propagate to state stp1 and collect a reward rew
[rew,stp1] = stNac2stp1(st,at,wind,sideII,sideJJ,s_end);
%fprintf('stp1=(%d,%d); rew=%3d...\n',stp1(1),stp1(2),rew);
% pick the greedy action from state stp1:
stp1i = sub2ind( [sideII,sideJJ], stp1(1), stp1(2) );
% make the greedy action selection:
[dum,atp1] = max(Q(stp1i,:));
if( rand<epsilon ) % explore ... with a random action
    tmp=randperm(nActions); atp1=tmp(1);
end
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*Q(stp1i,atp1) - 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) );
    break;
end
%update (st,at) pair:
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
st = stp1; sti = stp1i; at = atp1;

%pause;
end % end policy while
end % end episode loop

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function [rew,stp1] = stNac2stp1(st,act,wind,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);

% get the wind amount:
theWind = wind(jj);

% incorporate any actions and fix our position if we end up outside the grid:
%
switch act
case 1,
    %
    % action = UP
    %
    stp1 = [ii-1-theWind,jj];
case 2,
    %
    % action = DOWN
    %
    stp1 = [ii+1-theWind,jj];
case 3,
    %
    % action = RIGHT
    %

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    stp1 = [ii-theWind,jj+1];
case 4
    %
    % action = LEFT
    %
    stp1 = [ii-theWind,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

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