

15-859(B) Machine Learning Learning finite state environments

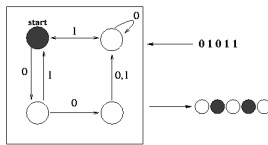
Avrim Blum
03/29/07

Consider the following setting

- Say we are a baby trying to figure out the effects our actions have on our environment...
 - Perform actions
 - Get observations
 - Try to make an internal model of what is happening.

A model: learning a finite state environment

- Let's model the world as a DFA. We perform actions, we get observations.
- Our actions can also change the state of the world. # states is finite.



Another way to put it

- We have a box with buttons and lights.



- Can press the buttons, observe the lights.
 - $lights = f(current\ state)$
 - $next\ state = g(button, current\ state)$
- **Goal: learn predictive model of device.**

Learning a DFA

In the language of our standard models...

- Asking if we can learn a DFA from Membership Queries.
 - Issue of whether we have counterexamples (Equivalence Queries) or not. [for the moment, assume not]
 - Also issue of whether or not we have a reset button. [for today, assume yes]

Learning DFAs



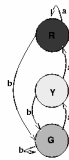
This seems really hard. Can't tell for sure when world state has changed.

Let's look at an easier problem first: state = observation.



An example w/o hidden state

2 actions: a, b.



Generic algorithm for lights=state:

- Build a model.
- While not done, find an unexplored edge and take it.

Now, let's try the harder problem!

Some examples

Example #1 (3 states)

Example #2 (3 states)

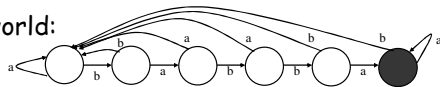
Can we design a procedure to do this in general?

One problem: what if we always see the same thing? How do we know there isn't something else out there?

Our model:

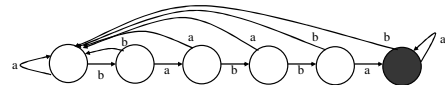


Real world:



Called "combination-lock automaton"

Can we design a procedure to do this in general?



Combination-lock automaton: basically simulating a conjunction.

This means we can't hope to efficiently come up with an exact model of the world from just our own experimentation. (I.e., MQs only).

How to get around this?

- Assume we can propose model and get counterexample. (MQ+EQ)
- Equivalently, goal is to be predictive. Any time we make a mistake, we think and perform experiments. (MQ+MB)
- Goal is not to have to do this too many times. For our algorithm, total # mistakes will be at most # states.

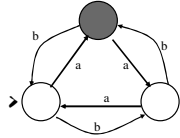
Algorithm by Dana Angluin

(with extensions by Rivest & Schapire)

- To simplify things, let's assume we have a RESET button. [Back to basic DFA problem]
- Next time, we'll see how to get rid of that.

The problem (recap)

- We have a DFA:

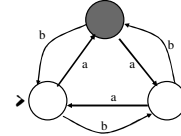


- $observation = f(current\ state)$
- $next\ state = g(button, prev\ state)$
- Can feed in sequence of actions, get observations. Then resets to start.
- Can also propose/field-test model. Get counterexample.

Key Idea

Key idea is to represent the DFA using a state/experiment table.

		experiments	
		λ	a
states	λ	<input type="checkbox"/>	<input checked="" type="checkbox"/>
	a	<input checked="" type="checkbox"/>	<input type="checkbox"/>
	b	<input type="checkbox"/>	<input type="checkbox"/>
transitions	aa	<input type="checkbox"/>	<input type="checkbox"/>
	ab	<input type="checkbox"/>	<input checked="" type="checkbox"/>
	ba	<input type="checkbox"/>	<input checked="" type="checkbox"/>
	bb	<input checked="" type="checkbox"/>	<input type="checkbox"/>



Key Idea

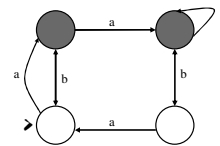
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	bb	<input checked="" type="checkbox"/>	<input type="checkbox"/>



The algorithm

We'll do it by example...



Algorithm (formally)

Begin with $S = \{\lambda\}, E = \{\lambda\}$.

- Fill in transitions to make a hypothesis FSM.
- While exists $s \in SA$ such that no $s' \in S$ has $row(s') = row(s)$, add s into S , and go to 1.
- Query for counterexample z .
- Consider all splits of z into (p_i, s_i) , and replace p_i with its predicted equivalent $\alpha_i \in S$.
- Find $\alpha_i r_i$ and $\alpha_{i+1} r_{i+1}$ that produce different observations.
- Add r_{i+1} as a new experiment into E . go to 1.