Offline Reinforcement Learning for Customizable Visual Navigation

Anonymous Author(s)
Affiliation
Address
email

Abstract: Robotic navigation often requires not only reaching a distant goal, but also satisfying intermediate user preferences on the path, such as obeying the rules of the road or preferring some surfaces over others. Our goal in this paper is to devise a robotic navigation system that can utilize previously collect data to learn navigational strategies that are responsive to user-specified utility functions, such as preferring specific surfaces or staying in sunlight (e.g., to maintain solar power). To this end, we show how offline reinforcement learning can be used to learn reward-specific value functions for long-horizon navigation that can then be composed with planning methods to reach distant goals, while still remaining responsive to user-specified navigational preferences. This approach can utilize large amounts of previously collected data, which is relabeled with the task reward. This makes it possible to incorporate diverse data sources and enable effective generalization in the real world, without any simulation, task-specific data collection, or demonstrations. We evaluate our system, ReViND, using a large navigational dataset from prior work, without any data collection specifically for the reward functions that we test. We demonstrate that our system can control a real-world ground robot to navigate to distant goals using only offline training from this dataset, and exhibit behaviors that qualitatively differ based on the user-specified reward function.

Keywords: offline reinforcement learning, visual navigation

1 Introduction

Robotic navigation approaches aim to enable robots to navigate to user-specified goals in known and unknown environments. The *geometric* approach to this problem involves using a geometric map of the environment to plan a collision-free path towards the goal. The *learning-based* approach to this problem involves the robot learning to take actions by associating new inputs with prior navigational experience, typically through imitation learning (IL) or reinforcement learning (RL). In many practical navigational scenarios, the goal is not merely to *reach* a particular destination without collision, but to do so while maximizing some desired *utility measure*, which could include obeying the rules of the road, staying in a bike lane or off the lawn, maintaining safety, or even more esoteric goals such as remaining in direct sunlight for a solar-powered vehicle. In these cases, neither IL nor geometric navigation alone would suffice without strong assumptions on the nature of the task or task-specific near-optimal demonstrations, which may be difficult to obtain. RL can, in principle, address such challenges, but prior work on applying RL to robotic navigation relies on infeasible amounts of online data collection, or requires high-fidelity simulators for simulation to real world transfer. Is there a practical RL paradigm than can solve this challenge directly from real-world data?

RL from offline datasets [1] can address this challenge by learning policies from a dataset of previously collected trajectories. Importantly, given a previously collected diverse dataset of navigational

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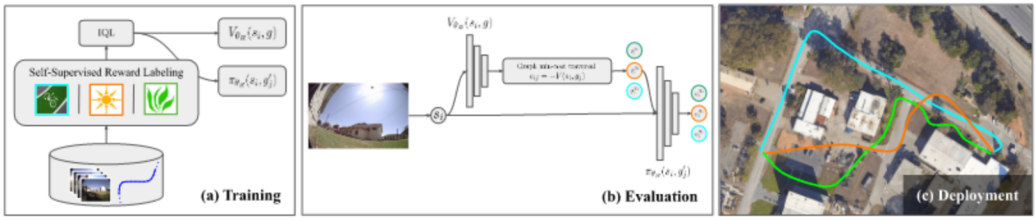

Figure 1: Customizable navigation with ReViND: (a) During training, we use an offline dataset of trajectories in conjunction with reward labels, specifying a target utility, to learn a Q-function. (b) During deployment, we use the values from this Q-function to generate a topological graph over observations, and plan through it. This plan incorporates the desired utility objective and can demonstrate varied behaviors (c) such as goal-reaching while driving in the sun, driving on grass, or more abstract objectives like following a bike lane.

trajectories, it is possible to relabel that dataset post-hoc with any reward function we want. Thus, a user could gather a large dataset from a variety of prior sources (e.g., other experiments, or even from the web), label it with their own reward function, train their own policy, and then deploy it, all *without ever having to collect their own data*. Since this approach can leverage large datasets, it may lead to significantly better generalization [scaling laws papers?] than methods that require much more tightly curated data, such as imitation methods. How can we design a system to learn control policies from large datasets that can be immediately deployed onto a mobile robot?

In this paper, we describe a robotic learning system that performs visual navigation to distant goals (e.g. 100s of meters away) while also incorporating user-specified reward objectives. Our system consists of two parts: (i) an offline Q-learning algorithm [2] that can incorporate the desired preferences in the learned Q-function and trains a policy operating directly on raw visual observations, and (ii) a topological representation of the environment, where nodes are represented by the raw visual observations and the connectivity between them is described by the learned value function (see system overview in Fig. 1). While the Q-function alone may only be sufficient to learn accurate navigational startegies over short horizons [3], combining it with a topological graph allows scaling to large environments by searching for a sequence of nodes to the goal that maximizes the desired objective at a coarse-level. The policy derived from the Q-function is subsequently used to navigate between the nodes, while also maximizing the specified objective at the lower-level.

The primary contribution of this work is ReViND, a robotic system for **Re**inforcement learning for **Vi**sual **N**avigation with prior **D**ata, that can utilize previously collected data in real-world environments, adopt behavior that is well-suited to user-specified reward functions (e.g., staying on the grass, staying in sunlight), and still be able to reach distant goals by combining planning and learning. We demonstrate that ReViND can readily incorporate high-level rewards, such as preferences for particular surfaces or staying in sunlight, and can perform goal-reaching in complex environments over hundreds of meters. ReViND is pre-trained on 30 hours of publicly available navigation data [4] and is deployed in the target environment *without* any on-policy data collection or fine-tuning. To the best of our knowledge, our results are the first demonstration of offline RL for navigation utilizing only previously available public datasets. Our experiments show that ReViND demonstrates markedly different goal-reaching behaviors by tweaking the reward objectives, while outperforming policies trained with imitation learning and model-free reinforcement learning.

2 Related Work

Robotic navigation has been studied from perspective of mapping, planning, imitation learning, and reinforcement learning. Classical navigation methods first acquire a geometric map, and then use this map to plan collision-free paths [5]. The map can be built up incrementally, including with intelligent exploration strategies that maximize information gain or otherwise optimize for faster map acquisition [6–17]. Such methods often aim to map out the entire environment first and then execute specific navigational tasks, though it is also possible to perform target-driven exploration, where the map is built in the course of navigating to a specific goal [18, 19]. However, all such

methods are fundamentally geometric: the task is defined as reaching some destination, rather than in terms of semantic reward functions that we consider in this work.

Similarly, many learning-based approaches to navigation also focus on largely geometric tasks, such as the "PointGoal" task [20], though they often utilize reinforcement learning methods that in principle can accommodate any reward function. The more severe issue with such methods is that RL algorithms can require a large amount of online experience (e.g., millions or even billions of trials) [20–22]. A method that requires a million 1-minute episodes would take more than 1.5 years of nonstop real-world collection, making it poorly suited for learning from scratch directly in the real world. Therefore, such methods typically require simulation, transfer, and other additional components []. An alternative for encoding specific user preferences into a learning-based method is to employ imitation learning []. While imitation learning can enable a user to define their desired behavior through the demonstrations, such demonstrations are time-consuming to gather, and must be recollected for each new reward function. In contrast, our offline RL method utilizes previously collected datasets, which we show is practical for real-world robots, and relabels the same dataset with different reward functions, which means no reward-specific data collection is needed.

Prior offline RL work has proposed a number of algorithms that can utilize previously collected data [1, 2, 23, 23–27]. Our goal is not to develop a new offline RL algorithm, but rather to explore their application to robotic navigation tasks. Most prior robotics applications of such methods include multi-task learning for manipulation [28–32]. Unlike these works, our focus is specifically on how a single dataset can be reused to enable long-horizon navigation with different user preferences. To that end, we combine our approach with graph-based search to reach distant goals, which we show significantly improves over direct use of the learned policy, and utilize the same exact data to optimize different reward functions. While prior work has also explored the use of offline data with varying reward functions [33, 34], we address significantly longer horizon tasks by incorporating model-free RL and graph search.

Our use of graph search in combination with RL parallels prior work that integrates graph search into both supervised skill learning methods [35, 36] and reinforcement learning [3, 37]. However, our method differs from these works in two ways. First, while these prior works use the value function to estimate the temporal distance between pairs of nodes in the graph, we specifically exploring using a variety of objectives. More importantly, we use offline RL, whereas prior work uses either supervised regression for distances, or online RL. To our knowledge, our work is the first to combine topological graphs with RL for arbitrary reward functions, and the first to combine them with offline RL.

3 Offline Reinforcement Learning for Long-Horizon Robotic Navigation

Our system combines offline learning of reward-specific value functions with topological planning over a graph constructed from prior experience in a given environment, so as to enable a robot to navigate to distant goals while maximizing user-specified rewards. The learned value function is used not only to supervise a local policy that chooses reward-maximizing actions, but also as a way to evaluate edge costs on a graph constructed from past experience. The graph is then used to plan a path, and the policy is used to execute the action to reach the first subgoal on that path. Structurally, this resembles SoRB [3], but with two critical changes: the use of offline RL to learn value functions from data, and the ability to handle various reward functions rather than just finding minimum length paths.

3.1 Problem Statement and Assumptions

The robot's task is defined in the context of a goal-conditioned MDP, with state observations $s \in \mathcal{S}$, actions $a \in \mathcal{A}$, and goals $g \in \mathcal{G}$. The robot receives a reward $r(s_t)$ at each time step t, which depends on the degree to which it is satisfying user preferences (e.g., staying on the graph), with an additional bonus for reaching the goal. The objective can be expressed as maximizing the total reward of the robot's executed path, since the reward accounts for both the desired utility and goal

reaching. We discuss specific rewards in Section 4. The state observations consist of RGB images from the robot's forward-facing camera and a 2D GPS coordinate, the actions are 2D steering and throttle commands, the goal is a 2D GPS coordinate expressed in the robot's frame of reference. In this setting, reinforcement learning methods will learn policies of the form $\pi(a_t|s_t, g_t)$, though our approach will not command the final task goal g_t directly, but instead will use a planning method to determine intermediate subgoals, which in practice makes it significantly easier to reach distant goals. To enable this sort of planning, we make an additional assumption that parallels prior work on combining RL with graph search [3, 36]: we assume that the robot has access to prior experience from the current environment that it can use to build a topological graph that describes its connectivity. Intuitively, this corresponds to a kind of "mental map" that describes which landmarks are reachable from which other landmarks. Importantly, we do *not* assume that this graph is manually constructed or provided: the algorithm constructs the graph automatically using an uncurated set of observations recorded from prior drive-throughs of the environment. In our experiment, these traversals are done via teleoperation, though they could also be performed via autonomous exploration, and our method could be extended to handle unseen environments by integrating the exploration procedures discussed in prior work [4].

3.2 Reinforcement Learning from Offline Data

Offline RL algorithms learn policies from static datasets. In our implementation we use implicit Q-learning (IQL) [2], though our approach is compatible with any value-based offline RL algorithm. We summarize offline RL in general and IQL specifically in this section. Given a dataset $\mathcal{D} = \{(s_i, a_i, r_i, s'_i) \mid i = 1 \ldots N\}$, the goal of offline RL is to learn a policy that optimizes the sum of discounted future rewards without any additional interactions with the environment. IQL involves fitting two neural networks, Q_θ and V_ψ, where $Q_\theta(s, a, g)$ approximates the Q-function of an *implicit* policy that maximizes the previous Q-function, and V_ψ represents the corresponding value function. The Q-function is updated by minimizing squared error against the next time step value function, with the objective

$$L(\theta) = \mathbb{E}_{(s,a,s')\sim\mathcal{D}, g\sim p(g|s)}[(\gamma V_\psi(s', g) + r(s, a, g) - Q_\theta(s, a, g))^2],$$

where $p(g|s)$ is a goal distribution, which we will discuss later. The value function $V_\psi(s, g)$ should be trained to correspond to $Q_\phi(s, a, g)$ for the optimal action a that maximizes the value at s, but directly computing $\max_a Q_\phi(s, a, g)$ is likely to select an "adversarial" out-of-distribution action that leads to erroneously large values, since the static dataset does not permit $Q_\phi(s, a, g)$ to be trained on all possible actions [1, 2, 26]. Therefore, IQL employs an *implicit* expectile update, with a loss function given by

$$L(\psi) = \mathbb{E}_{(s,a)\sim\mathcal{D}, g\sim p(g|s)}[L_2^\tau(Q_\theta(s, a, g) - V_\psi(s', g))],$$

where $L_2^\tau(u) = |\tau - \mathbb{1}(u < 0)|u^2$. This can be shown to approximate the maximum over *in-distribution* actions [2], but does not require ever querying out-of-sample actions during training. To instantiate this method, it remains only to select $p(g|s)$.

Goal relabeling. The IQL algorithm is not goal-conditioned [2], and the dataset was not collected with a goal-reaching policy, so the goals must be selected post-hoc with some sort of *relabeling strategy*. While a variety of relabeling strategies have been proposed in prior work [3, 32, 38–40], we follow prior work on offline RL for goal-reaching [32] and simply set the goal to states that are observed in the dataset in the same trajectory at time steps subsequent to a given sample s_i. In our implementation, we select this time step at random between 10 and 70 time steps after s_i (the total trajectory lengths are typically around 80 steps). Algorithm 1 outlines pseudocode for training the Q-function with IQL.

Long-horizon control. Instead of directly using the policy learned with IQL, in this paper we use the IQL value function to obtain edge costs for a graph used for topological planing. The standard IQL method directly extracts a reactive policy from the Q-function. However, we found that in the real world, this approach was unable to reach goals farther than 20m, or 80 time steps. A

deeper analysis of the system revealed that, while the policy and values learned by the IQL agent are valid over shorter horizons, they degrade rapidly as the horizon increases. This is not surprising, because like all value-based methods, IQL assumes that s represents a Markovian state. But this assumption becomes increasingly violated for long-horizon tasks with first-person images: while goals that are within line of sight of the robot are relatively simple, goals that require navigating around obstacles tend to fail if using the policy directly. In the next subsection, we will discuss how we can use a topological graph as a sort of "nonparametric memory" of the environment to alleviate this challenge, enabling our method to reach distant goals.

3.3 Long-Horizon Reward Maximization with a Topological Graph

To enable long-horizon navigation, we combine the value function learned via offline RL with a topological graph built from prior observations in a given environment. As discussed previously, we assume that the robot has a limited amount of prior experience in the test environment that can be used to build a "mental map," corresponding to a graph where nodes are observations and edges represent the cumulative reward the robot will accumulate as it travels from one node to another. Note that this graph is topological rather than geometric: the nodes are image observations, and the connectivity is determined by the learned value function. We do not use the data from the test environment to finetune the value functions, only to construct the graph.

The graph $\mathcal{G}$ is constructed in the same way as prior work on graph-based navigation (see Shah et al. [36] for the closest prior method): each state observation s_i in the test environment corresponds to a node n_i, and each edge e_{ij} receives a cost corresponding to $C(e_{ij}) = -V_\psi(s_i, s_j)$.[1] We further filter these edges based on the GPS coordinates of the nodes to eliminate *wormholes* arising due to optimistic value estimates. For more details on how the graph is constructed, please see Appendix B. Given an overall task goal, we add it to the graph as an additional node n_G, along with a node representing the robot's current state, and then use Dijkstra's algorithm to compute the shortest path with these edge costs. We then use the policy learned via offline RL to navigate to the first node along this path. Algorithm 2 outlines pseudocode for this procedure.

In our implementation, we use goal-conditioned reward functions of this form:

$$R(s_t, a_t, g) = \begin{cases} -k_t(s_t) & \forall s_t \neq g \\ 0 & \text{otherwise.} \end{cases} \tag{1}$$

where $k_t(s_t) > 0$ is always positive to ensure that the planner actually reaches the goal.

Proposition 3.1 *If we recover the optimal value function $V^*(s, s')$ for short-horizon goals s' (relative to s), and $\mathcal{G} = \mathcal{S}$ (all states exist in the graph), and the MDP is deterministic with $\gamma = 1$, then finding the minimum-cost path in the graph $\mathcal{G}$ with edge-weights $-V^*(s, s')$ recovers the optimal path, that is, a policy π that maximizes $V^*(s, g)$.*

Proof (sketch): The Bellman equation can be used to write the cost of the minimal-cost path in the graph with edge-weights $-V(s, s')$: $J^*(s, g) = \min_{s'}[-V(s, s') + J^*(s', g)] = -\max_{s'}[V(s, s') - J^*(s', g)]$. We can further expand $V(s, s')$ into a sum of rewards induced by the policy π and then rearrange the terms to obtain a similar optimality equation for V^* that demonstrates that $J^*(s, g) = -V^*(s, g)$.

While the above proposition is in some sense an obvious statement (and derived under strong assumptions), it provides some degree of confidence that our proposed method is *consistent*, in the sense that in the limit of unlimited data it will eventually obtain the optimal solution.

[1] In our actual implementation, goals are defined only in terms of GPS coordinates, rather than the full image, so technically the second argument is only the GPS coordinate of s_j, which we found to be sufficient, though extending the method to use the full image is a simple modification

Algorithm 1 Training ReViND

Initialize parameters ψ, θ, $\hat{\theta}$, ϕ.
for each gradient step **do**
  Sample a mini-batch $\{(s_i, a_i, r_i, s_i')\}$
  for each sample **do**
    $T \leftarrow T \in D \mid s_i \in T$
    $g_i \leftarrow \text{SampleGoal}(T, s_i)$
    $s_i, s_i' \leftarrow \text{Relabel}(s_i, s_i', g_i)$
    $r_i \leftarrow \text{Reward}(s_i, g_i)$
  $\psi \leftarrow \psi - \lambda_V \nabla_\psi L_V(\psi)$
  $\theta \leftarrow \theta - \lambda_Q \nabla_\theta L_Q(\theta)$
  $\hat{\theta} \leftarrow (1-\alpha)\hat{\theta} + \alpha\theta$

Algorithm 2 Deploying ReViND

Inputs: current observation obs $:= \{\text{img}, x\}$, set of past observations $\mathcal{N} := \{n_1, \ldots, n_m\}$, IQL agent $\{Q, V, \pi\}$, goal node $n_G \in \mathcal{N}$
$\mathcal{G} \leftarrow \text{ConstructGraph}(\mathcal{N}, V)$
while not $\text{IsClose}(\text{obs}, n_G)$ **do**
  $\text{UpdateGraph}(\text{obs})$
  $w_1, \ldots, w_k \leftarrow \text{DijkstraSearch}(\text{obs}, n_G)$
  for $t = 1, \ldots, H$ **do**
    goal vector = $\text{GetRelative}(x, w_1)$
    $\text{RunPolicy}(\text{img, goal})$ ▷ runs on robot
    obs ← next observation

4 System Evaluation

We now describe our system and experiments that we use to evaluate ReViND in real-world environments with a variety of utility functions. Our experiments evaluate ReViND's ability to incorporate diverse objectives and learn customizable behavior for long-horizon navigation, and compare it alternative methods for learning navigational skills from offline datasets.

4.1 Mobile Robot Platform

We implement ReViND on a Clearpath Jackal UGV platform (see Fig. 1). The sensor suite consists of a 6-DoF IMU, a GPS unit for approximate localization, and wheel encoders to estimate local odometry. The robot observes the environment using a forward-facing 170° field-of-view RGB camera. Compute is provided by an NVIDIA Jetson TX2 computer, with the offline RL controller running on-board. Our method uses only the monocular RGB images from the on-board camera and unfiltered GPS measurements.

4.2 Offline Trajectory Dataset and Self-Supervised Labeling

The ability to utilize offline datasets enables ReViND to learn navigation behavior directly from existing datasets — which may be expert teleoperated or collected via an autonomous exploration policy — without collecting *any* new data. To emphasize this, we train ReViND using 30 hours of publicly available robot trajectories collected using a randomized data collection procedure in an office park [4]. To utilize this data with our method, we relabel it with several different reward labels corresponding to three behaviors: simple shortest-path goal-reaching, driving in the sun (to emulate a solar-powered vehicle that needs sunlight), and driving on grass. We automatically generate labels for "sunny" and "grassy" observations by simple image processing operations in the HSV color space. We implement these rewards via additive bonus to the negative rewards which corresponds to reducing the penalty for traversing these areas. For more details, see Appendix A. As discussed in Sec. 3.2, we use IQL to learn the value functions and policies for each task.

Figure 3 illustrates the values learned by the Q-function for reaching goals that are ∼10m away. The value estimates corresponding to the three different utility functions estimate markedly different traversability costs. For example, $V_{\text{dist+sun}}$ predicts a lower cost (i.e., a higher value) for sunny observations, indicating that this value function prefers such paths.

4.3 Learning Varied Behaviors with ReViND

We now evaluate our method both in terms of its ability to tailor the navigational strategy to the provided reward, and in terms of how it compares to prior approaches and baselines. We test ReViND in five suburban environments for a large number of goal-reaching tasks. While these environments are visually similar to the offline training data, they exhibit dynamic elements such as humans, moving automobiles, and changes in the appearance of grass and trees across the seasons. In each evaluation

Figure 2: Comparison of policies for different reward functions learned by ReViND. Left: an overhead map (not available to the method), with grassy areas indicated with green shading. Note that the policy for the "sunny" reward chooses a significantly different path through a concrete parking lot without tree cover, while the policy for the "grassy" reward takes frequent detours to drive on lawns. Right: first person images during each traversal, with the chosen path indicated with colored lines.

environment, we first construct a topological graph by manually driving the robot and collecting visual and GPS observations. The nodes of this graph are obtained by sub-sampling these observations, such that they are 10–30m apart, and the edge connectivity is determined by the corresponding value estimates. Note that the Q-function is *not updated* with this data, it is only used to build the graph. Once the graph is constructed, the robot is tasked with reaching a goal location, where it follows Alg. 2 to search for a path through the graph, and then executes it via the learned policy. Fig. 2 shows the paths taken by policies corresponding to the different reward functions for a specific start-goal pair. The overhead image is not available to ReViND and is only provided for illustration.

Our results show that utilizing value functions for different rewards from ReViND leads to significantly different paths through the environment. For example, the "sunny" reward function causes a large detour through a parking lot without tree cover, while the "grassy" reward causes frequent detours to drive on loans. All of the policies successfully avoid obstacles and collisions and successfully reach the goal. In Table 1 we provide a quantitative summary of the behavior of the method for each reward function, showing success weighted by path length (SPL, which corresponds to an optimality measure that awards higher scores to successful runs with the shortest route length), the average value of the grass reward, and the average value of sun reward for trials corresponding to each reward function (note that these rewards are normalized to maximum of 1). As expected, we see that the values of these metrics strongly covary with the commanded reward.

Figure 3: The learned values for different utilities, shown here as horizontal bar plots, can incorporate diverse objectives, and are used downstream by ReViND to infer edge connectivity in the topological graph. E.g. a solar robot would perceive goals in a sunny environment (right) as favorable due to lower distance estimates, and prefer a route that avoids shadows.

Next, we compare ReViND to four baselines, each trained on the same offline dataset. These approaches represent natural points of comparison for our method, and include prior imitation learning and RL methods, as well as a prior graph-based method that does not use RL. Since our approach is (to our knowledge) the first to combine RL with arbitrary rewards and topological graph search, no prior approach supports both graphs and arbitrary rewards. All methods have access to egocentric images and GPS, and command future waypoints to the robot.

Agent Utility	SPL	$\mathbb{E}R_{\text{grass}}$	$\mathbb{E}R_{\text{sun}}$
R_{dist}	**0.87**	0.16	0.61
$R_{\text{dist}} + R_{\text{grass}}$	0.84	**0.86**	0.39
$R_{\text{dist}} + R_{\text{sun}}$	0.64	0.05	**0.68**

Table 1: ReViND learns custom behaviors that maximize the desired utility.

Behavioral Cloning (BC): A goal-conditioned imitation policy that maps images and goals to control actions [41]. *This baseline does not incorporate reward information.*

Filtered BC (fBC): A similar goal-conditioned BC policy that incorporates reward information by filtering the training data, picking only trajectories with the top 50% aggregate rewards [42].

ViNG: A graph-based navigation system that combines a goal-conditioned BC policy and distance function with a topological graph [36]. *This baseline does not incorporate reward information.*

Method	Avg. Distance (m)	$\mathbb{E}R_{\text{grass}}$
BC	13.7	0.03
fBC	22.5	0.23
IQL [2]	19.3	0.38
ViNG [36]	134.6	0.05
(Ours)	**188.6**	**0.66**

Table 2: Avg. distance before disengagement and expected utility for driving on grass. ReViND successfully reaches all goals while maximizing utility.

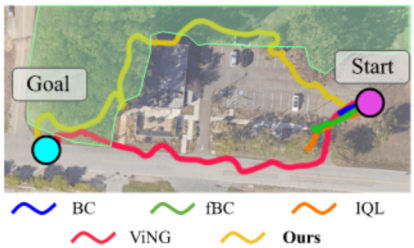

Figure 4: Qualitatively, only ReViND reaches the goal while prioritizing grassy terrain (shaded green).

IQL: A baseline that uses only the learned Q-function, without a topological graph [2].

Fig. 4 shows the qualitative behavior exhibited by the different systems for maximizing the "grassy" reward function. IQL and Filtered BC can incorporate the reward function into the policy, but since they rely entirely on a reactive policy for navigation, they are unable to determine how to navigate toward the goal, and exhibit meaningless bee-lining behavior. Using a graph search to find a minimum distance path, ViNG can reach the goal, but does not satisfy the reward function. Only ReViND is successful in navigating to the goal while taking a short detour that maximizes the desired objective, demonstrating affinity to grassy terrains. We provide a quantitative evaluation of these methods in Table 2, showing the average distance traveled by each method over all test trials prior to disengagement (which occurs when there is high risk of collision), as well as the average value of the "grass" reward. BC, fBC, and IQL, all exhibit bee-lining behavior, causing them to drive directly towards the goal — this leads to collisions with the curb, tree etc. and hence, early disengagements. The presence of a graph in ViNG and ReViND enables more interesting navigation behavior and collision-free paths. ReViND is able to drive up to 200m without disengagements while maximizing the utility measure by driving over grassy lawns.

5 Discussion

We presented ReViND, a robotic navigation system that uses offline reinforcement learning in combination with graph search to reach faraway goals while optimizing arbitrary user-specified reward functions. We showed that ReViND can be trained on a navigational dataset collected in prior work and, when this dataset is relabeled with a variety of reward functions, ReViND can exhibit distinct behavior, preferring certain terrains or environment conditions during the traversal. Our experiments show that ReViND is responsive to the specified reward function, and significantly outperforms prior methods that either do not utilize graph search and rely entirely on reactive policies, or else utilize graphs without RL and therefore do not support arbitrary rewards. We hope that our work will provide a step toward robotic learning methods that routinely reuse previously collected data, while still accomplishing new tasks and maximizing new user-specified reward functions. Such methods in principle can exhibit effective generalization in the real world through their ability to incorporate large and diverse previously collected datasets, while still flexibly solving new tasks.

Limitations: While ReViND supports a variety of reward functions, it has a number of limitations. First, all of the data must be labeled with the provided reward. While in principle this can even be done manually (since the method is fully offline), in practice it is much more practical to implement the reward function programmatically. In future work, accommodating preferences, textual commands, or other more natural modes of specifying the utility function would make the method more practical. Second, the behavior learned by ReViND does depend critically on the data that is provided. For example, if all provided data drives on roads, then it is impossible for the policy to learn how to drive off-road, since the relevant experience is simply unavailable. Combining ReViND with online exploration and finetuning may address this limitation in the future. Lastly, we evaluate ReViND in settings where the graph is built from previously seen experience. An exciting direction for future work would be to combine ReViND with a method for exploring a new environment to search for a goal, while maximizing the user-specified reward, for example by constructing the graph on the fly [4].

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