Teaching by Demonstration Supplementary Materials

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Appendix 1: An Example with 2 Goals

Suppose we have a 3x2 gridworld with two possible terminal goals (X and Y) and a starting position as shown in Figure 1i. We assume no step costs and $\gamma = .99$. We restrict our analysis to trajectories of length 2 that terminate at a goal state. Thus there are 4 trajectories considered.

(i) (ii)

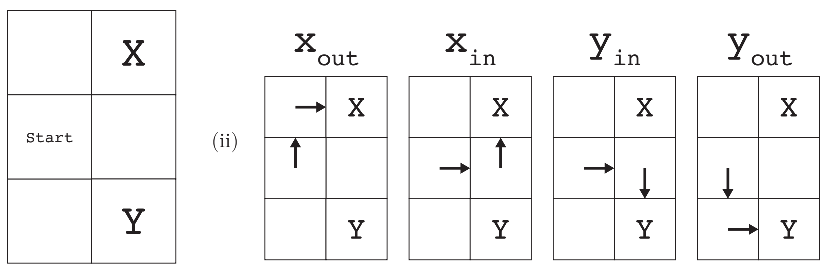

Figure 1: (i) Gridworld with 2 possible goal states (labeled X and Y) and a single starting state. (ii) All trajectories of length 2 that terminate at a goal state.

Proof

The purpose of this proof is to show that certain trajectories have higher probability of being chosen by a demonstrator who is "showing" as opposed to "doing" a task, even when all trajectories enter a goal. The prior probability over goals is uniform.

The following inequalities for a goal $g \in G = \{X, Y\}$ given a trajectory $j \in J = \{x_{in}, x_{out}, y_{in}, y_{out}\}$ will hold when a softmax policy or ϵ-greedy policy is used to calculate the standard planning distribution:

$$P_{\text{Doing}}(x_{out} \mid X) \geq P_{\text{Doing}}(x_{in} \mid X) > 0 \tag{1}$$

$$P_{\text{Doing}}(x_{in} \mid Y) > P_{\text{Doing}}(x_{out} \mid Y) > 0. \tag{2}$$

An observer watching a standard planner uses Bayes rule to infer the goal being pursued:

$$P_{\text{Observing}}(G = g \mid J = j) = \frac{P_{\text{Doing}}(J = j \mid G = g)}{\sum_{g'} P_{\text{Doing}}(J = j \mid G = g')}. \tag{3}$$

The inequalities in (1) and (2) entail the following inequality[1]:

$$\frac{P_{\text{Doing}}(x_{out} \mid X)}{P_{\text{Doing}}(x_{out} \mid X) + P_{\text{Doing}}(x_{out} \mid Y)} > \frac{P_{\text{Doing}}(x_{in} \mid X)}{P_{\text{Doing}}(x_{in} \mid X) + P_{\text{Doing}}(x_{in} \mid Y)}. \tag{4}$$

$$P_{\text{Observing}}(X \mid x_{out}) > P_{\text{Observing}}(X \mid x_{in}). \tag{5}$$

That is, observing x_{out} provides better evidence that X is the goal than observing x_{in}. Since an agent that is showing an observer will choose as follows:

$$P_{\text{Showing}}(J = j \mid G = g) = \frac{P_{\text{Observing}}(G = g \mid J = j)^{\alpha}}{\sum_{j'} P_{\text{Observing}}(G = g \mid J = j')^{\alpha}}, \tag{6}$$

then,

$$\frac{P_{\text{Observing}}(X \mid x_{out})^{\alpha}}{\sum_{j'} P_{\text{Observing}}(X \mid j')^{\alpha}} > \frac{P_{\text{Observing}}(X \mid x_{in})^{\alpha}}{\sum_{j'} P_{\text{Observing}}(X \mid j')^{\alpha}} \tag{7}$$

$$P_{\text{Showing}}(x_{out} \mid X) > P_{\text{Showing}}(x_{in} \mid X) \tag{8}$$

Intuitively, the different probabilities of x_{out} and x_{in} when Y is the goal allows a showing agent to "break the symmetry" between x_{out} and x_{in} when X is the goal. Analogous calculations can show that $P_{\text{Showing}}(y_{out} \mid Y) > P_{\text{Showing}}(y_{in} \mid Y)$.

[1] For $a, b, c, d > 0$ if $a \geq b$ and $c > d$, then:

$$\begin{gathered} ac > bd \\ ab + ac > bd + ab \\ a(b + c) > b(a + d) \\ \frac{a}{a + d} > \frac{b}{b + c} \end{gathered}$$

Appendix 2: Experiment 2 Model Fits

Table 1: Experiment 2 Maximum Median Likelihood Model Parameters

		Doing Condition							
		ooo	oox	oxo	oxx	xoo	xox	xxo	xxx
Standard Planning Model	λ	0.02	0.02	0.02	0.02	0.02	0.04	0.02	0.02
Pedagogical Model	l_{max}	7	7	9	9	9	7	9	7
	α	2	1	1	1	1	20	1	1
	p_{min}	10^{-6}	10^{-10}	10^{-6}	10^{-7}	10^{-6}	10^{-5}	10^{-7}	10^{-10}
	λ	0.05	0.20	0.10	0.20	0.10	0.20	0.05	0.20
		Showing Condition							
		ooo	oox	oxo	oxx	xoo	xox	xxo	xxx
Standard Planning Model	λ	0.08	0.10	0.02	0.02	0.30	0.09	0.02	0.02
Pedagogical Model	l_{max}	7	9	9	9	11	9	9	7
	α	1	10	20	1	1	5	1	1
	p_{min}	10^{-10}	10^{-7}	10^{-7}	10^{-7}	10^{-10}	10^{-5}	10^{-7}	10^{-10}
	λ	0.20	0.05	0.05	0.20	0.20	0.05	0.05	0.20

Note: The codes for the reward functions refer to which tiles were safe (o) and which were dangerous (x) with the ordering <orange, purple, cyan>.