

VALUE PRESERVING STATE-ACTION ABSTRACTIONS: SUPPLEMENTAL MATERIAL

David Abel¹, Nathan Umbanhowar¹, Khimya Khetarpal², Dilip Arumugam³,
Doina Precup², Michael L. Littman¹
{david_abel, umbanhowar}@brown.edu, khimya.khetarpal@mail.mcgill.ca,
dilip@cs.stanford.edu, dprecup@cs.mcgill.ca, mlittman@cs.brown.edu
¹Brown University, USA
²McGill University, CA
³Stanford University, USA

1 PROOFS

We here present proofs of each introduced result and Table 1 summarizing notation.

Theorem 1. *Every deterministic policy defined over abstract states and ϕ -relative options, $\pi_{\phi, \mathcal{O}_\phi} : \mathcal{S}_\phi \rightarrow \mathcal{O}_\phi$, induces a unique Markov policy in the ground MDP, $\pi_{\phi, \mathcal{O}_\phi}^\downarrow : \mathcal{S} \rightarrow \mathcal{A}$. We denote $\Pi_{\phi, \mathcal{O}_\phi}^\downarrow$ as the set of policies in the original MDP representable by the pair (ϕ, \mathcal{O}_ϕ) via this mapping.*

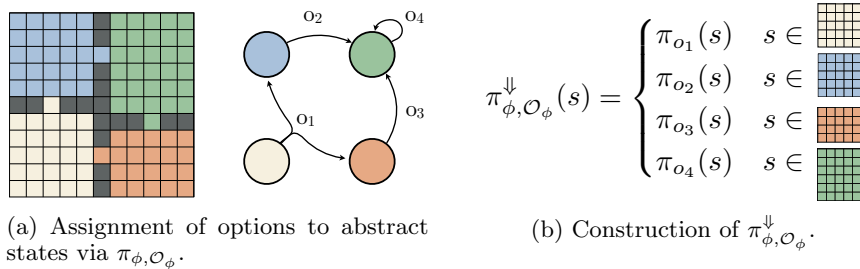
Proof. Consider an arbitrary deterministic policy $\pi_{\phi, \mathcal{O}_\phi}$. By definition, this policy assigns one option to each abstract state. Let \mathcal{O}_π denote the set of options this policy assigns.

By construction of ϕ -relative options, for every ground state $s \in \mathcal{S}$ there is one unique option $o_{\phi(s)} \in \mathcal{O}_\pi$ that can be executed in s .

Therefore, we construct a policy $\pi_{\phi, \mathcal{O}_\phi}^\downarrow$ as the combination of option policies in \mathcal{O}_π . Specifically, letting $\pi_{o_{\phi(s)}}$ denote the option policy of the option in \mathcal{O}_π that is assigned to $\phi(s)$:

$$\pi_{\phi, \mathcal{O}_\phi}^\downarrow(s) = \pi_{o_{\phi(s)}}(s) \quad (16)$$

This construction is visualized in Figure 2. □



(a) Assignment of options to abstract states via $\pi_{\phi, \mathcal{O}_\phi}$.

(b) Construction of $\pi_{\phi, \mathcal{O}_\phi}^\downarrow$.

Figure 2: The process of inducing a grounded policy $\pi_{\phi, \mathcal{O}_\phi}^\downarrow$ from $\pi_{\phi, \mathcal{O}_\phi}$.

Theorem 2. (Main Result) *For any ϕ such that $L(\phi) \leq \varepsilon_\phi$, the two introduced classes of ϕ -relative options satisfy:*

$$L(\phi, \mathcal{O}_{\phi, Q_\varepsilon}) \leq \frac{\varepsilon_Q}{1 - \gamma}, \quad L(\phi, \mathcal{O}_{\phi, M_\varepsilon}) \leq \frac{\varepsilon_R + |\mathcal{S}| \varepsilon_T \text{VMAX}}{1 - \gamma}. \quad (17)$$

ϕ	A state abstraction function.
\mathcal{O}_ϕ	A set of ϕ -relative options.
$\pi_{\phi, \mathcal{O}_\phi}$	A policy that maps each abstract state to an option.
$\pi_{\phi, \mathcal{O}_\phi}^\downarrow$	A policy over \mathcal{S} and \mathcal{A} , induced by $\pi_{\phi, \mathcal{O}_\phi}$.
H_n	A hierarchy of depth n , denoting $(\phi^{(n)}, \mathcal{O}_\phi^{(n)})$.
$\phi^{(n)}$	A list of n state abstractions, where $\phi_i : \mathcal{S}_{\phi, i-1} \rightarrow \mathcal{S}_{\phi, i}$.
ϕ_i	The i -th state abstraction in a list $\phi^{(n)}$.
ϕ^i	The result of applying the first i state abstractions to s , $\phi_i(\dots \phi_1(s))$.
$\mathcal{S}_{\phi, i}$	The i -th abstract state space.
V_i^π	The value function of level i policy π defined according to $R_i, T_i, \mathcal{O}_{\phi, i}, \mathcal{S}_{\phi, i}$.
$\mathcal{O}_{\phi, i}$	The options available at level i , with each option component defined over states in $\mathcal{S}_{\phi, i-1}$.
R_i	The reward function of level i .
T_i	The reward function of level i .
π_i	The policy over level i of the hierarchy
π_i^\downarrow	A policy over $\mathcal{S}_{\phi, i-1}$ and $\mathcal{O}_{\phi, i-1}$, induced by π_i .
$\pi_i^{\downarrow\downarrow}$	A policy over \mathcal{S} and \mathcal{A} , induced by π_i .

Table 1: Notation

We prove this claim using two separate proofs, the first targets the $\mathcal{O}_{\phi, Q_\varepsilon^*}$ class of options, and the second, $\mathcal{O}_{\phi, M_\varepsilon}$.

Proof. $(L(\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}) \leq \frac{\varepsilon Q}{1-\gamma})$

Consider $L(\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}) = \min_{\pi_{\phi, \mathcal{O}_\phi}^\downarrow \in \Pi_{\phi, \mathcal{O}_\phi}^\downarrow} \max_{s \in \mathcal{S}} |V^*(s) - V^{\pi_{\phi, \mathcal{O}_\phi}^\downarrow}(s)|$. Since $V^*(s) \geq V^\pi(s)$ for all π , we henceforth drop the absolute value for convenience.

To proceed, we first define $o_{s_\phi}^*$ to be the ϕ -relative option that executes π^* in every state and terminates when it leaves the abstract state s_ϕ :

$$o_{s_\phi}^* := \forall s \in \mathcal{S} : \langle \mathcal{I}_{o^*}(s) \equiv \phi(s) = s_\phi, \quad (18)$$

$$\beta(s) \equiv \phi(s) \neq s_\phi, \quad (19)$$

$$\pi(s) = \pi^*(s). \quad (20)$$

Note that since $o_{s_\phi}^*$ always chooses actions according to π^* , that $Q_{s_\phi}^*(s, o_{s_\phi}^*) = V^*(s)$ (where $Q_{s_\phi}^*$ is defined according to Equation 6).

Then, by the Q_ε^* predicate, we can construct a policy over abstract states and options $\mu_{\phi, \mathcal{O}_\phi} \in \Pi_{\phi, \mathcal{O}_\phi}$ with the following property:

$$\forall s_\phi \in \mathcal{S}_\phi, s \in s_\phi : Q_{s_\phi}^*(s, o_{s_\phi}^*) - Q_{s_\phi}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \leq \varepsilon Q. \quad (21)$$

Note that $\mu_{\phi, \mathcal{O}_\phi}(s_\phi)$ outputs an option. As in Equation 21, we henceforth denote $s_\phi = \phi(s)$ and correspondingly $s'_\phi = \phi(s')$.

Then it must be the case that

$$L(\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}) \leq \max_{s \in \mathcal{S}} V^*(s) - V^{\mu_{\phi, \mathcal{O}_\phi}^\downarrow}(s). \quad (22)$$

Let $Q_t^*(s, o)$ denote the expected discounted reward of executing option o , then executing t options under $\mu_{\phi, \mathcal{O}_\phi}$, then following the optimal policy thereafter. Note that

$$\lim_{t \rightarrow \infty} Q_t^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) = V^{\mu_{\phi, \mathcal{O}_\phi}^\downarrow}(s), \quad (23)$$

because $Q_t^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi))$ is the expected discounted reward of executing $t+1$ options under $\mu_{\phi, \mathcal{O}_\phi}$, then following the optimal policy thereafter.

We next show by induction on t that

$$\max_{s \in \mathcal{S}} V^*(s) - V^{\mu_{\phi, \mathcal{O}_\phi}^\downarrow}(s) = \max_{s \in \mathcal{S}} \lim_{t \rightarrow \infty} V^*(s) - Q_t^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \leq \frac{\varepsilon_Q}{1-\gamma}. \quad (24)$$

In particular, we wish to show that

$$\forall t \in \mathbb{N} : \max_{s \in \mathcal{S}} V^*(s) - Q_t^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \leq \sum_{i=0}^t \varepsilon_Q \gamma^i. \quad (25)$$

(Base Case)

When $t = 0$, for all $s \in \mathcal{S}$,

$$Q_0^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) = Q_{s_\phi}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)), \quad (26)$$

because both quantities represent the expected discounted reward of executing the option $\mu_{\phi, \mathcal{O}_\phi}(s_\phi)$ then following the optimal policy thereafter. It follows that

$$\max_{s \in \mathcal{S}} V^*(s) - Q_0^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) = \max_{s \in \mathcal{S}} V^*(s) - Q_{s_\phi}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)), \quad (27)$$

$$= \max_{s \in \mathcal{S}} Q_{s_\phi}^*(s, o_{s_\phi}^*) - Q_{s_\phi}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)), \quad (28)$$

$$\leq \varepsilon_Q, \quad (29)$$

$$= \sum_{i=0}^0 \varepsilon_Q \gamma^i, \quad (30)$$

where the inequality holds by definition of $\mu_{\phi, \mathcal{O}_\phi}$.

(Inductive Case)

We assume as the inductive hypothesis that

$$\max_{s \in \mathcal{S}} V^*(s) - Q_k^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \leq \sum_{i=0}^k \varepsilon_Q \gamma^i, \quad (31)$$

and want to show that

$$\max_{s \in \mathcal{S}} V^*(s) - Q_{k+1}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \leq \sum_{i=0}^{k+1} \varepsilon_Q \gamma^i. \quad (32)$$

To begin, fix $s \in \mathcal{S}$ and consider

$$V^*(s) - Q_{k+1}^*(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) \quad (33)$$

$$= V^*(s) - \left(R_o(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) + \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) Q_k^*(s', \mu_{\phi, \mathcal{O}_\phi}(s'_\phi)) \right) \quad (34)$$

$$= V^*(s) - R_o(s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) - \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_\phi}(s_\phi)) Q_k^*(s', \mu_{\phi, \mathcal{O}_\phi}(s'_\phi)) \quad (35)$$

where R_o and T_o indicate the reward and multi-time option models from Sutton et al. (1999).

Now, subtract and add $\sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi}))V^*(s')$:

$$= V^*(s) - R_o(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) - \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi}))V^*(s') \quad (36)$$

$$+ \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi}))V^*(s') - \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi}))Q_k^*(s', \mu_{\phi, \mathcal{O}_{\phi}}(s'_{\phi})) \quad (37)$$

$$= V^*(s) - Q_{s_{\phi}}^*(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \quad (38)$$

$$+ \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) [V^*(s') - Q_k^*(s', \mu_{\phi, \mathcal{O}_{\phi}}(s'_{\phi}))] \quad (39)$$

$$= Q_{s_{\phi}}^*(s, \mathcal{O}_{s_{\phi}}^*) - Q_{s_{\phi}}^*(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \quad (40)$$

$$+ \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) [V^*(s') - Q_k^*(s', \mu_{\phi, \mathcal{O}_{\phi}}(s'_{\phi}))] \quad (41)$$

$$\leq \varepsilon_Q + \sum_{s' \in \mathcal{S}} T_o(s'|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) [V^*(s') - Q_k^*(s', \mu_{\phi, \mathcal{O}_{\phi}}(s'_{\phi}))], \quad (42)$$

by definition of $\mu_{\phi, \mathcal{O}_{\phi}}$. Continuing, we have that:

$$= \varepsilon_Q + \sum_{s' \in \mathcal{S}} \sum_{n=1}^{\infty} \mathbb{P}(s', n|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \gamma^n [V^*(s') - Q_k^*(s', \mu_{\phi, \mathcal{O}_{\phi}}(s'_{\phi}))] \quad (43)$$

$$\leq \varepsilon_Q + \sum_{s' \in \mathcal{S}} \sum_{n=1}^{\infty} \mathbb{P}(s', n|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \gamma^n \sum_{i=0}^k \varepsilon_Q \gamma^i, \quad (44)$$

$$(45)$$

by the inductive hypothesis. Then:

$$= \varepsilon_Q + \gamma \sum_{s' \in \mathcal{S}} \sum_{n=0}^{\infty} \mathbb{P}(s', n+1|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \gamma^n \sum_{i=0}^k \varepsilon_Q \gamma^i \quad (46)$$

$$= \varepsilon_Q + \gamma \sum_{i=0}^k \varepsilon_Q \gamma^i \sum_{s' \in \mathcal{S}} \sum_{n=0}^{\infty} \mathbb{P}(s', n+1|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \gamma^n \quad (47)$$

$$\leq \varepsilon_Q + \gamma \sum_{i=0}^k \varepsilon_Q \gamma^i \cdot 1 \quad (48)$$

$$= \sum_{i=0}^{k+1} \varepsilon_Q \gamma^i, \quad (49)$$

since $\mathbb{P}(s', n+1|s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi}))$ is a probability distribution and γ is less than 1.

All together, we've shown that $V^*(s) - Q_{k+1}^*(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \leq \sum_{i=0}^{k+1} \varepsilon_Q \gamma^i$ for all $s \in \mathcal{S}$, which implies that

$$\max_{s \in \mathcal{S}} V^*(s) - Q_{k+1}^*(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \leq \sum_{i=0}^{k+1} \varepsilon_Q \gamma^i, \quad (50)$$

as desired.

It follows by induction that

$$\forall t \in \mathbb{N} : \max_{s \in \mathcal{S}} V^*(s) - Q_t^*(s, \mu_{\phi, \mathcal{O}_{\phi}}(s_{\phi})) \leq \sum_{i=0}^t \varepsilon_Q \gamma^i. \quad (51)$$

Therefore,

$$L(\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}) \leq \max_{s \in \mathcal{S}} V^*(s) - V^{\mu_{\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}}^\downarrow}(s) \quad (52)$$

$$= \max_{s \in \mathcal{S}} \lim_{t \rightarrow \infty} V^*(s) - Q_t^*(s, \mu_{\phi, \mathcal{O}_{\phi, Q_\varepsilon^*}}(s_\phi)) \quad (53)$$

$$\leq \lim_{t \rightarrow \infty} \sum_{i=0}^t \varepsilon_Q \gamma^i \quad (54)$$

$$= \frac{\varepsilon_Q}{1 - \gamma}, \quad (55)$$

which completes the proof. □

.....

Proof. $(L(\phi, \mathcal{O}_{\phi, M_\varepsilon}) \leq \frac{\varepsilon_R + |\mathcal{S}| \varepsilon_T \text{VMAX}}{1 - \gamma})$

Fix $s \in \mathcal{S}$. Let $s_\phi = \phi(s)$. Consider any ϕ -relative option o_1 that initiates in s_ϕ . Then by the M_ε predicate, there exists an option $o_2 \in \mathcal{O}_\phi$ such that

$$\|T_{s, o_1}^{s'} - T_{s, o_2}^{s'}\|_\infty \leq \varepsilon_T \text{ AND } \|R_{s, o_1} - R_{s, o_2}\|_\infty \leq \varepsilon_R. \quad (56)$$

Now, we consider the difference in optimal Q-values between o_1 and o_2 . We first have that:

$$\begin{aligned} Q_{s_\phi}^*(s, o_1) &= R(s, \pi_{o_1}(s)) + \gamma \sum_{s' \in \mathcal{S}} T(s' | s, \pi_{o_1}(s)) \left(\mathbb{1}(s' \in s_\phi) Q_{s_\phi}^*(s', o_1) + \mathbb{1}(s' \notin s_\phi) V^*(s') \right) \\ &= R_o(s, o_1) + \sum_{s' \in \mathcal{S}} T_o(s' | s, o_1) V^*(s'). \end{aligned} \quad (57)$$

By symmetry,

$$Q_{s_\phi}^*(s, o_2) = R_o(s, o_2) + \sum_{s' \in \mathcal{S}} T_o(s' | s, o_2) V^*(s'). \quad (58)$$

Therefore,

$$\begin{aligned} |Q_{s_\phi}^*(s, o_1) - Q_{s_\phi}^*(s, o_2)| &= |R_o(s, o_1) - R_o(s, o_2) + \sum_{s' \in \mathcal{S}} T_o(s' | s, o_1) V^*(s') - \\ &\quad \sum_{s' \in \mathcal{S}} T_o(s' | s, o_2) V^*(s')| \\ &\leq |R_o(s, o_1) - R_o(s, o_2)| + \left| \sum_{s' \in \mathcal{S}} (T_o(s' | s, o_1) - T_o(s' | s, o_2)) V^*(s') \right| \\ &\leq |R_o(s, o_1) - R_o(s, o_2)| + \sum_{s' \in \mathcal{S}} |T_o(s' | s, o_1) - T_o(s' | s, o_2)| |V^*(s')| \\ &\leq \varepsilon_R + |\mathcal{S}| \varepsilon_T \text{VMAX}, \end{aligned} \quad (59)$$

by the model similarity assumption. We have now shown that options with similar models have similar Q-values with $\varepsilon_Q = \varepsilon_R + |\mathcal{S}| \varepsilon_T \text{VMAX}$. Therefore, by the previous result,

$$L(\phi, \mathcal{O}_{\phi, M_\varepsilon}) \leq \frac{\varepsilon_R + |\mathcal{S}| \varepsilon_T \text{VMAX}}{1 - \gamma}. \quad (60)$$

□

.....

Lemma 1. *Every deterministic policy π_i defined according to the i -th level of a hierarchy, H_n , induces a unique policy in the ground MDP, which we denote π_i^\downarrow .*

Proof. The result follows from an identical strategy to the proof of Theorem 1. □

.....

Theorem 3. *Consider two algorithms:*

1. A_ϕ : given an MDP M , outputs a ϕ .
2. $A_{\mathcal{O}_\phi}$: given M and a ϕ , outputs a set of options \mathcal{O} such that $L(\phi, \mathcal{O}) \leq \varepsilon_{\mathcal{O}}$.

Then, under Assumptions 1 and 2, by repeated application of A_ϕ and $A_{\mathcal{O}_\phi}$, we can construct a hierarchy of depth n such that

$$L(H_n) = n(\kappa + \ell), \tag{61}$$

where ℓ is some upper bound on $\varepsilon_\phi + \varepsilon_{\mathcal{O}}$ (and is the same value that appears in Assumption 2).

Proof. We present the proof of the bound for a two level hierarchy, but the same strategy generalizes to n levels via induction.

Let ℓ be the known upper bound for $L(\phi, \mathcal{O})$. Then:

By Theorem 2:
$$\min_{\pi_1 \in \Pi_1} \|V_0^* - V_0^{\pi_1^\downarrow}\|_\infty \leq \ell \tag{62}$$

By Assumption 1:
$$\forall \pi_1 \in \Pi_1 : \|V_0^{\pi_1^\downarrow} - V_1^{\pi_1}\|_\infty \leq \kappa \tag{63}$$

Letting $\pi_1^\diamond = \arg \min_{\pi_1 \in \Pi_1} \|V_0^* - V_0^{\pi_1^\downarrow}\|_\infty$, by Assumption 2:
$$\min_{\pi_2^\downarrow \in \Pi_2^\downarrow} \|V_1^{\pi_1^\diamond} - V_1^{\pi_2^\downarrow}\|_\infty \leq \ell \tag{64}$$

By Assumption 1
$$\forall \pi_2^\downarrow \in \Pi_2^\downarrow : \|V_1^{\pi_2^\downarrow} - V_0^{\pi_2^\downarrow}\|_\infty \leq \kappa \tag{65}$$

Therefore, by the triangle inequality:

$$\min_{\pi_2 \in \Pi_2} \|V_0^* - V_0^{\pi_2}\|_\infty \leq 2\kappa + 2\ell. \tag{66}$$

□

REFERENCES

- David Abel, D. Ellis Hershkowitz, and Michael L. Littman. Near optimal behavior via approximate state abstraction. In *ICML*, pp. 2915–2923, 2016.
- David Abel, Dilip Arumugam, Kavosh Asadi, Yuu Jinnai, Michael L. Littman, and Lawson L.S. Wong. State abstraction as compression in apprenticeship learning. In *AAAI*, 2019.
- David Andre and Stuart J Russell. State abstraction for programmable reinforcement learning agents. In *AAAI*, pp. 119–125, 2002.
- Pierre-Luc Bacon, Jean Harb, and Doina Precup. The option-critic architecture. In *AAAI*, 2017.

- Aijun Bai and Stuart Russell. Efficient reinforcement learning with hierarchies of machines by leveraging internal transitions. In *IJCAI*, 2017.
- Aijun Bai, Siddharth Srivastava, and Stuart J Russell. Markovian state and action abstractions for MDPs via hierarchical MCTS. In *IJCAI*, pp. 3029–3039, 2016.
- Andrew G Barto and Sridhar Mahadevan. Recent advances in hierarchical reinforcement learning. *Discrete event dynamic systems*, 13(1-2):41–77, 2003.
- Emma Brunskill and Lihong Li. PAC-inspired option discovery in lifelong reinforcement learning. In *ICML*, pp. 316–324, 2014.
- Pablo Samuel Castro and Doina Precup. Automatic construction of temporally extended actions for MDPs using bisimulation metrics. In *EWRL*, 2011.
- Kamil Ciosek and David Silver. Value iteration with options and state aggregation. *arXiv:1501.03959*, 2015.
- Peter Dayan and Geoffrey E Hinton. Feudal reinforcement learning. In *NeurIPS*, pp. 271–278, 1993.
- Thomas Dean and Robert Givan. Model minimization in Markov decision processes. In *AAAI*, 1997.
- Richard Dearden and Craig Boutilier. Abstraction and approximate decision-theoretic planning. *Artificial Intelligence*, 89(1):219–283, 1997.
- Thomas G Dietterich. Hierarchical reinforcement learning with the MAXQ value function decomposition. *Journal of Artificial Intelligence Research*, 2000.
- Norm Ferns, Prakash Panangaden, and Doina Precup. Metrics for finite Markov decision processes. In *UAI*, 2004.
- Ronan Fruit and Alessandro Lazaric. Exploration–exploitation in MDPs with options. *AISTATS*, 2017.
- Jesse Hostetler, Alan Fern, and Tom Dietterich. State aggregation in MCTS. In *AAAI*, 2014.
- Marcus Hutter. Extreme state aggregation beyond MDPs. In *International Conference on Algorithmic Learning Theory*, pp. 185–199. Springer, 2014.
- Nan Jiang, Alex Kulesza, and Satinder Singh. Abstraction selection in model-based reinforcement learning. In *ICML*, pp. 179–188, 2015.
- Nicholas K Jong and Peter Stone. State abstraction discovery from irrelevant state variables. In *IJCAI*, pp. 752–757, 2005.
- Nicholas K Jong and Peter Stone. Hierarchical model-based reinforcement learning: R-max+MAXQ. In *ICML*, pp. 432–439, 2008.
- Anders Jonsson and Andrew G Barto. Automated state abstraction for options using the U-tree algorithm. In *NeurIPS*, pp. 1054–1060, 2001.
- George Konidaris and Andrew G Barto. Building portable options: Skill transfer in reinforcement learning. In *IJCAI*, 2007.
- George Konidaris, Leslie Pack Kaelbling, and Tomas Lozano-Perez. From skills to symbols: Learning symbolic representations for abstract high-level planning. *Journal of Artificial Intelligence Research*, 2018.
- Lihong Li, Thomas J Walsh, and Michael L Littman. Towards a unified theory of state abstraction for MDPs. In *ISAIM*, 2006.

- Marlos C Machado, Marc G Bellemare, and Michael Bowling. A Laplacian framework for option discovery in reinforcement learning. In *ICML*, 2018.
- Sultan Javed Majeed and Marcus Hutter. Performance guarantees for homomorphisms beyond Markov decision processes. *AAAI*, 2019.
- Timothy Mann and Shie Mannor. Scaling up approximate value iteration with options: Better policies with fewer iterations. In *ICML*, pp. 127–135, 2014.
- Timothy A Mann, Shie Mannor, and Doina Precup. Approximate value iteration with temporally extended actions. *Journal of Artificial Intelligence Research*, 2015.
- Ofir Nachum, Shixiang Gu, Honglak Lee, and Sergey Levine. Near-optimal representation learning for hierarchical reinforcement learning. *ICLR*, 2019.
- Maillard Odalric-Ambrym, Phuong Nguyen, Ronald Ortner, and Daniil Ryabko. Optimal regret bounds for selecting the state representation in reinforcement learning. In *ICML*, 2013.
- Ronald Parr and Stuart J Russell. Reinforcement learning with hierarchies of machines. In *NeurIPS*, pp. 1043–1049, 1998.
- Balaraman Ravindran. SMDP homomorphisms: An algebraic approach to abstraction in semi Markov decision processes. 2003.
- Richard S Sutton, Doina Precup, and Satinder Singh. Between MDPs and semi-MDPs: A framework for temporal abstraction in reinforcement learning. *Artificial Intelligence*, 1999.
- Jonathan Taylor, Doina Precup, and Prakash Panagaden. Bounding performance loss in approximate MDP homomorphisms. In *NeurIPS*, 2008.
- Saket Tiwari and Philip S Thomas. Natural option critic. *AAAI*, 2019.
- Nicholay Topin, Nicholas Halmeyer, Shawn Squire, John Winder, James MacGlashan, et al. Portable option discovery for automated learning transfer in object-oriented Markov decision processes. In *IJCAI*, 2015.