Do What Nature Did To Us: Evolving Plastic Recurrent Neural Networks For Task Generalization

Fan Wang†, Hao Tian†, Haoyi Xiong†, Hua Wu†, Yang Cao‡, Yu Kang‡, Haifeng Wang†
† Baidu Inc.
‡ Department of Automation, University of Science and Technology of China
†{wang.fan, tianhao, xionghaoyi, wu_hua, wanghaifeng}@baidu.com
‡{forrest, kangduyu}@ustc.edu.cn

Abstract

While artificial neural networks (ANNs) have been widely adopted in machine learning, researchers are increasingly obsessed by the gaps between ANNs and biological neural networks (BNNs). In this paper, we propose a framework named as Evolutionary Plastic Recurrent Neural Networks (EPRNN). Inspired by BNN, EPRNN composes Evolution Strategies, Plasticity Rules, and Recursion-based Learning all in one meta learning framework for generalization to different tasks. More specifically, EPRNN incorporates with nested loops for meta learning— an outer loop searches for optimal initial parameters of the neural network and learning rules; an inner loop adapts to specific tasks. In the inner loop of EPRNN, we effectively attain both long term memory and short term memory by forging plasticity with recursion-based learning mechanisms, both of which are believed to be responsible for memristance in BNNs. The inner-loop setting closely simulate that of BNNs, which neither query from any gradient oracle for optimization nor require the exact forms of learning objectives. To evaluate the performance of EPRNN, we carry out extensive experiments in two groups of tasks: Sequence Predicting, and Wheeled Robot Navigating. The experiment results demonstrate the unique advantage of EPRNN compared to state-of-the-arts based on plasticity and recursion while yielding comparably good performance against deep learning based approaches in the tasks. The experiment results suggest the potential of EPRNN to generalize to variety of tasks and encourage more efforts in plasticity and recursion based learning mechanisms.

1 Introduction

Artificial Neural Networks (ANNs) achieve huge success in machine learning. Despite being initially inspired by Biological Neural Networks (BNNs), the optimization paradigm for ANNs has diverged from that of BNNs. BNNs are believed to learn through plastic rules (Gerstner et al., 1993), also known as Hebb’s rule (Hebb [1949]). In contrast, the optimization of ANNs is dominated by gradient descent methods, the evidences of which are less revealed in BNNs. Though up to now gradient descent methods are the most efficient optimizers for ANNs, their limitations are beginning to attract attentions, including the problems of catastrophic forgetting, over consumption of data, and the requirement for manual efforts in designing target functions. Those challenges are becoming the main impedance for further development of machine intelligence.

Recent studies show that under proper meta-parameter optimization, both recursion (Santoro et al., 2016; Mishra et al., 2018) and plasticity (Soltoggio et al., 2008; Najarro & Risi, 2020) can be valid alternatives to train ANNs for task generalization. Unlike gradient descending, both of the two learning mechanisms work in an unsupervised manner, without requiring exact forms of learning objectives, which are believed to more closely simulate BNNs.

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Recursion based learning typically employs recurrent neural networks (RNN), LSTM (Hochreiter & Schmidhuber 1997), and self-attention (Mishra et al. 2018; Chen et al. 2021) layers as learners. Learning takes place within the feed forward pass. The information are updated in the hidden states instead of the parameters. Recursion are found to be extremely sample efficient in generalized supervised tasks (Santoro et al. 2016), zero-shot generalization in language (Brown et al. 2020), and reinforcement learning (Mishra et al. 2018; Chen et al. 2021) when compared with various type of gradient descent methods. So far among those learners, though self-attention based learners such as Transformers have state-of-the-art performance, the computational costs for inference per step grow linearly with the sequence length, which makes them only available to relatively short sequences. On the other hand, recurrent learners such as RNN and LSTM have constant per-step inference costs, but suffer form poor asymptotic performances. That is, when sequences are getting longer, performances no longer improve or even deteriorate. This is partly due to the limitation of the memory spaces. For instance, an recurrent hidden layer of size \( n \) has a memory of scale \( O(n) \). In contrast, its parameters scale with \( O(n^2) \), which makes parameter-updating more powerful as learning mechanisms than recursion-only.

Prior to our work, evolving plasticity (Soltoggio et al. 2008; Lindsey & Litwin-Kumar 2020; Yaman et al. 2021) has been proposed to reproduce the natural evolution and plasticity in simulation, as shown in Figure 1. Implementing plasticity is not straight-forward, unlike gradient-descent, plastic rules are not universal but have to be optimized beforehand, which is not possible without a further outer-loop optimizer over the inner-loop learning. Evolutionary algorithms (Zhang et al. 2011) are typically applied in the outer loop to search for meta-parameters shaping the learning rules, which can be regarded as information carried by genomes during evolution. Those optimized plasticity rules are then applied in the inner loop to further tune the parameter of NN for better adaptions to the environment. Due to the complexity in training, plasticity is insufficiently investigated and its potential is not well understood. Existing works on evolving plasticity are mainly focused on feed-forward layers. However, as recursion widely exists in BNNs, it is desirable to also investigate plasticity in recurrent connections.

Another motivation of combining recursion with plasticity is to simultaneously possess the merits of updating information in hidden states and in connection weights. Both recursion and plasticity mechanisms are believed to be relevant to memristance. While recursion that updates hidden states only is likely to be related to short-term memories, synaptic plasticity that updates connection weights is more related to long-term memories (Bliss & Lømo 1973; Mel 2002; Linares-Barranco & Serrano-Gotarredona 2009). Based on this motivation, we propose a new learning framework named as...
Table 1: A brief review of meta learning methods

| Methods                              | Inner Loop                         | Outer Loop                        |
|--------------------------------------|------------------------------------|-----------------------------------|
| Memory Augmented NN (Santoro et al., 2016) | Recursion                          | Gradient                          |
| MAML, (Finn et al., 2017)            | Gradient                           | Gradient                          |
| Reptile, (Nichol et al., 2018)       | Gradient                           | Average                           |
| Conditional Neural Processes, (Garnelo et al., 2018) | Average                           | Gradient                          |
| SNAIL, (Mishra et al., 2018)         | Gradient                           | Gradient                          |
| ES-MAML, (Song et al., 2019)         | Gradient, Hill Climbing            | Evolution                         |
| EPMLP, (Najarro & Risi, 2020)        | Plasticity                         | Evolution                         |
| EPRNN (ours)                         | Plasticity & Recursion             | Evolution                         |

*Evolutionary Plastic Recurrent Neural Networks (EPRNN)*. Specifically, we apply plastic rules in recurrent connections by utilizing the information of time-dependent hidden states. Then, following the natural evolution of intelligence (Fig. 1), in the outer loop we employ evolution strategies to search for proper initial parameters and plastic rules. To validate our proposal, we carry out experiments on two groups of tasks: *Sequence Predicting* and *Wheeled Robot Navigating*. We compared the proposed framework with the other recursion and gradient based learners. The experiment results show that EPRNN can surpass decent models such as LSTM using the most naive recurrent structures. Although the validated model structure is relatively simple, we believe that validating such prototypes is an important step toward more general cases.

## 2 Related Works

### 2.1 Meta Learning

Meta learning aims at building learning machines that gain experience using task-specific data over a distribution of tasks. Inspired by human and animal brains that are born with both embedded skills and capability of acquiring new skills, meta learning implements two nested learning loops: The outer learning loops optimize the meta that typically involves initial parameters (Finn et al., 2017; Song et al., 2019), learning rules (Zoph & Le, 2017; Najarro & Risi, 2020; Pedersen & Risi, 2021), and model structures (Soltoggio et al., 2008; Li & Malik, 2016) over a distribution of tasks; The inner learning loops adapt the model to specific task by utilizing the meta. According to different inner-loop optimizers, we roughly classify the methods into *model-based* and *parameter-updating* methods. The *model-based* methods do not update the parameters in the inner-loop, where learning is accomplished by updating the hidden states (e.g., recursion); The *parameter-updating* methods update the parameter in the inner-loop (e.g., gradient descent (MAML), plasticity). From this point of view, our method can be classified into both groups. A brief review of the typical meta learning paradigms is presented in Table 1.

### 2.2 Evolving Plasticity

The proposal of the learning mechanism of BNNs is initially raised by Hebb’s rule (Hebb, 1949), the most well-known part of which is “neurons fire together wire together”. It is further polished by Spike Time-Dependent Plasticity (STDP) (Gerstner et al., 1993) indicating that the signal of learning is dependent on the temporal patterns of the pre-synaptic spike and post-synaptic spike. Learning could also appear in inhibitory connections, also known as anti-hebbian (Barlow, 1989). Also, relationships between STDP and memristance are also investigated (Linares-Barranco & Serrano-Gotarredona, 2009). Since many of those rules are related to spiking neural networks (Ghosh-Dastidar & Adeli, 2009), to apply them to ANNs, simplified rules are proposed (Soltoggio et al., 2008) instead: given the pre-synaptic neuron state $X$ and post-synaptic neuron state $Y$, the connections between $X$ and $Y$ are updated by

$$\delta W = m[A \cdot XY + B \cdot X + C \cdot Y + D],$$

where $m$ is the output from neuron modulators that adjust the learning rates of plasticity, which is also inspired by previous discovery in BNNs.

Since plasticity rules can not be easily optimized with gradient-based methods (Miconi et al., 2018), evolutionary algorithms (Zhang et al., 2011) are naturally exploited in plasticity based ANNs.
Observation (i), \( W \), \( h \)

Some works also investigate the possibility of learning plastic rules without depending on the initial parameters \( [\text{Najarro \\ Risi} 2020 \text{, Yaman et al.} 2021] \). However, most of previous works related to plasticity are focused on feed forward layers only; Few of them did thorough comparison with the other learners in task generalization.

3 Algorithms

**Problem Settings.** We consider an agent (learner) that is dependent on meta-parameter \( \theta \). It has the capability of adapting itself to a distribution of tasks \( T_j \in T \) by interacting with the environment \( T_j \) through observation \( i_t \) and action \( a_t \). In K-shot learning, the agent is allowed to first observe samples of length \( K \) (this stage can be referred as meta-training-training, see \( [\text{Beaulieu et al.} 2020] \), then its fitness is calculated in meta-training-testing rollouts. In Generalized Supervised Learning tasks (GSL), the observations typically include features \( \{x_i, y_i\} \), and the labels are left out for predicting in the meta-training-testing stage (\( [\text{Santoro et al.} 2016] \text{, Garnelo et al.} 2018 \)). In Generalized Reinforcement Learning tasks (GRL), the observations typically include states \( \{s_i, a_{t-1}, r_{t-1}\} \), sometimes \( r_{t-1} \) can not be observed (\( [\text{Mishra et al.} 2018] \)). The goal of meta-training is to optimize \( \theta \) such that the agent achieves higher fitness in meta-training-testing. In meta-testing, similarly, the learned parameters are given meta-testing-training and meta-testing-testing in order, the performances in meta-testing-testing are evaluated.

**Plastic Recurrent Neural Networks (PRNN).** Given a sequence of observations \( i_1, ..., i_t, ... \), we first consider an recurrent neural network (RNN) that propagates forward and yields sequence of outputs \( a_t \) following:

\[
\begin{align*}
\hat{h}_{t+1} &= \sigma(W_t \cdot h_t + W_i \cdot i_t + b), \\
a_t &= f(h_{t+1})
\end{align*}
\]

where \( h_t \) is the hidden states at step \( t \). In PRNN, we kept \( W_t \) stationary, but we set \( W_t \) to be plastic, so that we add a subscript \( t \) to mark different \( W_t \) at different steps. Regarding \( h_t \) as pre-synaptic neuron states, and \( h_{t+1} \) as post-synaptic neuron states, by applying Equation [1] we update \( W_t \) with:

\[
\begin{align*}
W_{t+1} &= W_t + \delta W_t, \\
\delta W_t &= W_A \odot (\hat{h}_{t+1} \cdot h_t^T) + W_B \odot (m_t \cdot h_t^T) + W_C \odot (\hat{h}_{t+1} \cdot 1^T) + W_D \cdot m_t, \\
\hat{h}_{t+1} &= m_t \odot h_{t+1},
\end{align*}
\]

where we use \( \odot \) and \( \cdot \) to represent “element-wise multiplication” and “matrix multiplication” respectively. \( h \) and \( 1 \) are column vectors. \( W_A, W_B, W_C, W_D \) are collection of plastic rules of \( A, B, C, D \) from Equation [1] which has the same shape as \( W_t \). \( m_t \) is the neural modulators that adjusts the learning rates of plasticity. We calculate \( m_t \) by applying a neuron modulating layer denoted with:

\[
m_t = \sigma(W_h^{(m)} \cdot h_t + W_i^{(m)} \cdot i_t + b^{(m)}).
\]

![Figure 2: A sketch of the information flow in plastic recurrent neural networks (PRNN)](image-url)
A sketch of PRNN is presented in Figure 2. The main difference between PRNN and naive RNN is that PRNN updates both the hidden states and the connection weights during the forward pass.

**Evolving PRNN.** Given task \( T_j \in T \), by continuously applying Equation 2 to 7 over meta-training-training and meta-training-testing, the fitness is eventually dependent on the initial parameters, learning rules, and the sampled task \( T \), which is denoted as:

\[
\text{Fit}(\theta, T) = \text{Fitness}(i_{K+1}, a_{K+1}, i_{K+2}, a_{K+2}, \ldots) \tag{8}
\]

\[
W_i, W_0, W_A, W_B, W_C, W_D, W_{hi}^{(m)}, W_{iy}^{(m)}, b, b^{(m)} \in \theta \tag{9}
\]

Following Evolution Strategies (ES) (Salimans et al., 2017), in \( k \)th outer-loop iteration, we sample different tasks from \( T \), and meta-parameters \( b_{k,i} \) \( (i \in [1, n]) \) from the neighbourhoods of \( \theta_k \). We evaluate the fitness of sampled meta-parameters, and update the meta-parameters by applying:

\[
\theta_{k+1} = \theta_k + \frac{1}{n} \sum_{i=1}^{n} \text{Fit}(\theta_{k,i}, T_k)(\theta_{k,i} - \theta_k) \tag{10}
\]

**Why Recurrent Neural Networks?** As stated in Equation 1, plasticity in feed-forward-only NNs allows NNs to gain experiences from single-frame observation only. In cases of non-sequential GSL, the plasticity has chances to tune the connection weights to the specific task by relying on observing one single frame of data \( t_i = \{x_t, y_t\} \), since its information of the feature and the supervision is complete. However, in general cases, learning can not happen without summarizing sequences of observations. For instances, a human driver getting used to a new car through continuously interacting and observing. Moreover, in GRL, there are time lag between the observation of states and feed-backs. Recursion helps to summarize historical observations to give the correct update for the connection weights.

Although, compared with naive RNN, there are obviously bunches of more sophisticated neural structure such as GRU and LSTM, we believe it is more desirable to start from simplest recurrent structure to study the potential of combining recursion and plasticity.

### 4 Experiments

#### 4.1 Tasks for Evaluation

In generalized tasks, we have each task \( T_j \) dependent on some configuration parameters that are hidden from the agent. Below we introduce two groups of generalized tasks that we experiment on.

**Sequence Predicting** (Generalized Supervised Learning tasks). We randomly generate sequences of vectors \( y(t) = (y_1(t), \ldots, y_t(t)) \), where \( y_i(t) = A \sin(\frac{2\pi t}{n} + \phi_i) \), \( t = 1, 2, 3, \ldots \) and \( A_i \sim \mathcal{U}(1, 3) \), \( n_i \sim \mathcal{U}(10, 100) \), \( \phi_i \sim \mathcal{U}(0, 2\pi) \), and \( \mathcal{U}(a, b) \) represents the uniform distribution between \( a \) and \( b \). \( A \), \( n \) and \( \phi \) are hidden from the agent. The front part of the sequence \( y(1), y(2), \ldots, y(K) \) is exposed to the agent, and the left part \( y(K + 1), y(K + 2), \ldots, y(N) \) is to be predicted. The fitness is the opposite of mean square error (MSE) between the predicted sequence and the ground truth. We test the methods for comparison in four groups of tasks including \((l = 1, K = 10, N = 20), (l = 1, K = 25, N = 50), (l = 3, K = 10, N = 20), \) and \((l = 3, K = 25, N = 50)\) (see Figure 3(a)(b)).

**Wheeled Robot Navigating** (Generalized Reinforcement Learning tasks). The agent is to navigate a two-wheeled robot to a randomly generated goal in 2-D space \( g = (g_x, g_y) \). We assume that there is a signal transmitter on the goal and a receiver on the robot. The robot observes the signal intensity decided by \( A_1 = A_0 - k \cdot \log(d_i/d_0) + \epsilon \) (inspired by the attenuation for electromagnetic wave, see Friis (1946)), where \( d_i \) is the current distance between the robot and the goal, \( \epsilon \sim \mathcal{N}(0, \sigma) \) is the white noise in the observation. \( g_x, g_y, A_0, k \) are environment related configurations that is hidden from the agent. For each task, we sample configurations by \( g_x, g_y \sim \mathcal{U}(-0.5, 0.5), A_0 \sim \mathcal{U}(0.5, 2.0), \) and \( k \sim \mathcal{U}(0.1, 0.5) \). The action is the rotation speed of its two wheels that controls the orientation and velocity of the robot. The reward at each step is \( r_t = -d_t \), an episode terminates when the robot approaches the goal or steps reaches the maximum of 100. We also hide its own position and orientation from the agent, such that the agent relies on recording its own action the signal strength.
A robot to locate itself. We investigate three types of navigating circumstances with different level of noises in the observed signal: Low Noise ($\sigma = 0.01$), Median Noise ($\sigma = 0.05$), and High Noise ($\sigma = 0.2$) (see Figure 3(c)).

![Figure 3: A sketch of the trajectories of three sampled tasks.](image)

**4.2 Experiment Settings**

We add the following methods into comparison, the methods share exactly the same outer loop and differ in the inner loop.

- **ES-MAML** (Song et al., 2019): We use four gradient descent steps in the inner loop, the learning rate of each step is treated as meta-parameters which is to be optimized by the outer loop. As MAML can not utilize instant observation in zero-shot case, we show results of both **ES-MAML (zero-shot)** and **ES-MAML (one-rollout)** in Wheeled Robot Navigating. Except for ES-MAML, the other methods are measured with zero-shot meta-testing score only in Wheeled Robot Navigating.

- **ES-RNN**: Vanilla RNN as the inner loop learner.

- **ES-LSTM**: Long Short Term Memory (Hochreiter & Schmidhuber, 1997) as the inner loop learner.

- **EPMLP** (Soltoggio et al., 2018): Multi-Layer Perceptrons (MLP) with plasticity rules implemented.

- **EPMLP (Random)** (Najarro & Risi, 2020): The main difference with EPMLP is randomly setting the parameters of the plastic layers at the beginning of each inner loop instead of using fixed trainable initial parameters.

- **EPRNN (w/o m)**: Removing neuron modulator ($m_t$) from the plasticity rule in PRNN.

We add additional non-plastic fully connected layers before and after the plastic layers to increase the representation capability of the models. For fairness, we kept those layers identical for all compared methods. For every 100 outer loops in **meta training**, we add an extra **meta testing** epoch, evaluating the average fitness of current meta-parameters on testing tasks. Each run includes 15000 outer loops and 150 meta-testing epochs. Each result is concluded from independent 3 runs. Our code[1] relies on PARL[2] for parallelization. We leave the detailed illustration of the model structures and hyper-parameters in the Appendices.

**4.3 Results**

We present the experiment results in Figure 4 (In Table[2] and Table[3], we also list the summarized performance by averaging the Top-3 meta-testing scores in the latest 10 meta-testing epochs of each run over 3 independent runs). Generally, we can conclude that PRNN performs substantially better when compared with naive RNN. In some cases, it even produces better results compared with LSTM, despite the simpler model architecture. It is also interesting to notice that the gap between RNN and PRNN are smaller in shorter sequences or low-noise environments, but larger in more challenging

[1]https://github.com/WorldEditors/EvolvingPRNN
[2]https://github.com/PaddlePaddle/PARL
tasks with longer sequence or higher noise (In Wheeled Robot Navigating tasks, higher noise pushes the agent to maintain a longer memory in order to filter the noise and figure out the way to goal). This phenomenon reaffirms the lack of long-term memories in RNN, and shows that PRNN significantly improves this drawback. Comparing EPRNN (w/o m) with RNN and EPRNN clearly demonstrates that simple ABCD rule (without the neural modulator) may also work to some extent, but introducing the neuron modulator $m_t$ can further benefit the learner.

Among plasticity based methods, we show that recursion is more advantageous than MLP in evaluated tasks. It is also worth noticing that EPMLP and EPMLP (Random) perform steadily beyond the gradient-based learner (ES-MAML). In ES-MAML, the gradient can only be calculated after an episode is completed, while EPMLP is able to perform sequential learning even though no feedback is available during its lifetime. This demonstrates the possibility of surpassing human-designed gradient-based learning rules with automatically learned unsupervised rules. Moreover, comparison between EPMLP and EPMLP (Random) validate the proposal of [Najarro & Ris, 2020], implying the possibility of discovering global plastic learning rules instead of rules coupled with the initial parameters. Yet we see optimization of the initial parameters is still advantageous, which can also be validated by evidences in nature that the newborn lives already have certain embedded skills (e.g., Newborn human babies have reflexes of suckling and grasping; Foals can stand shortly after being born).

Figure 4: Plotting meta-testing scores against meta-training iterations.
As those weights are in relatively high dimension, we run t-SNE visualization to map $W_i$ to 2-D space and show their trajectories in Figure 5. We found that $W_i$ start from the same position and gradually move in different directions depending on the tasks. The final weights effectively capture environmental configuration that was hidden from the agent. Particularly, in Figure 5(d) for Wheeled Robot Navigating tasks, we can see that $W_i$ captures only the signal transmission patterns ($A_0, k$), but neglects the position of the goal ($g_x, g_y$). We guess that $A_0, k$ are important stationary patterns that helps the agent to interpret the observed signal strength ($A_t$), while the absolute position of goal is less important as its relative position to the robot is changing continuously. This is a clear demonstration showing that plasticity has done meaningful update on the connections weights depending on the tasks.

### Table 2: Summarized performances comparison in Sequence Predicting tasks

| Methods    | l=1,K=10,N=20 | l=1,K=25,N=50 | l=3,K=10,N=20 | l=3,K=25,N=50 |
|------------|---------------|---------------|---------------|---------------|
| ES-RNN     | $-0.385 \pm 0.060$ | $-1.228 \pm 0.191$ | $-1.273 \pm 0.009$ | $-1.811 \pm 0.015$ |
| ES-LSTM    | $-0.165 \pm 0.014$ | $-0.283 \pm 0.013$ | $-1.229 \pm 0.010$ | $-1.475 \pm 0.016$ |
| ES-MAML    | $-1.452 \pm 0.292$ | $-1.747 \pm 0.064$ | $-1.218 \pm 0.013$ | $-1.796 \pm 0.013$ |
| EPMLP      | $-0.732 \pm 0.031$ | $-1.185 \pm 0.045$ | $-1.339 \pm 0.004$ | $-1.735 \pm 0.013$ |
| EPRNN (Random) | $-1.233 \pm 0.115$ | $-1.319 \pm 0.035$ | $-1.489 \pm 0.023$ | $-1.788 \pm 0.003$ |
| EPRNN (w/o m) | $-0.114 \pm 0.012$ | $-0.208 \pm 0.025$ | $-1.107 \pm 0.015$ | $-1.430 \pm 0.019$ |

### Table 3: Summarized performances comparison in Wheeled Robot Navigating tasks

| Methods          | Low Noise ($\sigma = 0.01$) | Median Noise ($\sigma = 0.05$) | High Noise ($\sigma = 0.2$) |
|------------------|-----------------------------|--------------------------------|------------------------------|
| ES-RNN           | $-16.90 \pm 1.30$           | $-18.99 \pm 0.14$              | $-31.23 \pm 3.95$            |
| ES-LSTM          | $-14.04 \pm 0.08$           | $-15.50 \pm 0.58$              | $-22.53 \pm 0.45$            |
| ES-MAML (zero-shot) | $-37.18 \pm 0.45$           | $-37.91 \pm 0.80$              | $-37.90 \pm 0.05$            |
| ES-MAML (1 rollout) | $-23.10 \pm 0.46$           | $-29.21 \pm 0.46$              | $-37.12 \pm 0.12$            |
| EPMLP            | $-21.24 \pm 6.08$           | $-16.65 \pm 0.39$              | $-23.75 \pm 2.02$            |
| EPMLP (Random)   | $-13.02 \pm 0.19$           | $-18.25 \pm 0.23$              | $-28.85 \pm 1.1$             |
| EPRNN            | $-12.71 \pm 0.75$           | $-15.07 \pm 0.03$              | $-23.79 \pm 0.55$            |
| EPRNN (w/o m)    | $-14.93 \pm 0.49$           | $-16.72 \pm 0.33$              | $-24.11 \pm 0.34$            |

### 4.4 Analysis

To investigate whether plasticity rules update the connection weights as expected, we test the trained model with different tasks and record the updating trajectories of plastic connection weights $W_i$. As those weights are in relatively high dimension, we run t-SNE visualization to map $W_i$ to 2-D space and show their trajectories in Figure 5. We found that $W_i$ start from the same position and gradually move in different directions depending on the tasks. The final weights effectively capture environmental configuration that was hidden from the agent. Particularly, in Figure 5(d) for Wheeled Robot Navigating tasks, we can see that $W_i$ captures only the signal transmission patterns ($A_0, k$), but neglects the position of the goal ($g_x, g_y$). We guess that $A_0, k$ are important stationary patterns that helps the agent to interpret the observed signal strength ($A_t$), while the absolute position of goal is less important as its relative position to the robot is changing continuously. This is a clear demonstration showing that plasticity has done meaningful update on the connections weights depending on the tasks.

### 5 Conclusions

In this paper we present a nature-inspired learning framework composed of Evolution Strategies, Plastic rules, and Recursion. Experiment results show that plasticity can be effectively forged with recursion to enhance the learning capability. The proposed framework can achieve equivalent or even better performances compared with more sophisticated neural structures, by applying the simplest recurrent neural structures. Moreover, we also show that under proper meta parameters, plasticity has a chance to surpass gradient descent methods.

We believe the learning framework of Figure 1 can be extended to more sophisticated plastic rules and model structures, uncovering better learners in the future. Also, it would be more interesting if such framework can be validated in more complex environments such as natural language processing tasks and vision-related tasks. Finally, we are looking forward that this work can shed light to new paradigm of building intelligent machines and inspire more efforts in this line of research.
(a) Varying $A$ for task Sequence Predicting ($l=1$,$K=25$,$N=50$)
(b) Varying $n$ for task Sequence Predicting ($l=1$,$K=25$,$N=50$)
(c) Varying $\phi$ for task Sequence Predicting ($l=1$,$K=25$,$N=50$)
(d) Varying settings for task Wheeled Robot Navigating (Low Noise)

Figure 5: t-SNE visualization of the trajectories of the plastic connection weights $W_t$.

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Appendix

A.1 Model Architecture and Training Details

To maintain fairness for comparison, the model architectures of the compared methods are similar, where the differences lie in only one of their layers (Figure 6). We use 3 hidden layers for Sequence Predicting tasks and 4 hidden layers for Wheeled Robot Navigating tasks. For ES-MAML, we replace the PRNN layer with fully connected layer; For ES-RNN and ES-LSTM, we replace it with RNN and LSTM respectively; For EPMLP, we replace it with plastic fully connected layer, where the plasticity rule is stated by Equation 1, and the neural modulator $m$ is calculated by an additional dense layer with sigmoid activation. The hidden sizes of all the hidden layers are 64 (for LSTM it is 64 hidden states and 64 cell states).

Figure 6: A sketch of the model architectures for evaluated tasks

For Sequence Predicting tasks, the input observation and the output action has the dimension of $l$. In the meta-training-training and meta-testing-train stages, we use the ground truth $y_{t-1}$ as input observation; In the meta-training-test and meta-testing-test stages, its previous action ($a_{t-1}$) are taken as inputs. For Wheeled Robot Navigating tasks, the output action is the control command of its two wheels (a length 2 vector), the input observation is the concatenation of its previous action and the current observed signal intensity ($A_t$).

Figure 7: A sketch of the parallel training framework.

The training process is accelerated by utilizing the paralleling mechanism of PARL. We employ 400 workers (400 Intel(R) Xeon(R) CPU E5-2650) running inner-loops for 400 off-springs in each generation of the evolution, and additional 1 CPU to perform evolutionary update (shown in Figure 7(b)). It takes 3 to 12 hours for each run depending on the length of the inner loop and model architectures. Following the previous work (Salimans et al., 2017), we rank normalize the fitness among 400 workers. The learning rate $\alpha$ is set to $0.2$. The mutation is performed by adding independent Gaussian noises to each parameter. During the meta-training, we sample $B$ different tasks and 400 meta-parameters. Each worker run $B$ meta-training-training and $B$ meta-training-testing given the assigned meta-parameter, then the fitness is averaged. We set $B = 16$ for Sequence Predicting tasks, and $B = 4$ for Wheeled Robot Navigating tasks. For each meta-testing epoch, we evaluated the current meta parameters in newly sampled 1600 tasks.