A Minimalist Approach to Offline Reinforcement Learning

Scott Fujimoto\textsuperscript{1,2} \quad Shixiang Shane Gu\textsuperscript{2}  \\
\textsuperscript{1}Mila, McGill University  \quad \textsuperscript{2}Google Research, Brain Team  \\
scott.fujimoto@mail.mcgill.ca

Abstract

Offline reinforcement learning (RL) defines the task of learning from a fixed batch of data. Due to errors in value estimation from out-of-distribution actions, most offline RL algorithms take the approach of constraining or regularizing the policy with the actions contained in the dataset. Built on pre-existing RL algorithms, modifications to make an RL algorithm work offline comes at the cost of additional complexity. Offline RL algorithms introduce new hyperparameters and often leverage secondary components such as generative models, while adjusting the underlying RL algorithm. In this paper we aim to make a deep RL algorithm work while making minimal changes. We find that we can match the performance of state-of-the-art offline RL algorithms by simply adding a behavior cloning term to the policy update of an online RL algorithm and normalizing the data. The resulting algorithm is a simple to implement and tune baseline, while more than halving the overall run time by removing the additional computational overhead of previous methods.

1 Introduction

Traditionally, reinforcement learning (RL) is thought of as a paradigm for online learning, where the interaction between the RL agent and its environment is of fundamental concern for how the agent learns. In offline RL (historically known as batch RL), the agent learns from a fixed-sized dataset, collected by some arbitrary and possibly unknown process [Lange et al., 2012]. Eliminating the need to interact with the environment is noteworthy as data collection can often be expensive, risky, or otherwise challenging, particularly in real-world applications. Consequently, offline RL enables the use of previously logged data or leveraging an expert, such as a human operator, without any of the risk associated with an untrained RL agent.

Unfortunately, the main benefit of offline RL, the lack of environment interaction, is also what makes it a challenging task. While most off-policy RL algorithms are applicable in the offline setting, they tend to under-perform due to “extrapolation error”: an error in policy evaluation, where agents tend to poorly estimate the value of state-action pairs not contained in the dataset. This in turn affects policy improvement, where agents learn to prefer out-of-distribution actions whose value has been overestimated, resulting in poor performance [Fujimoto et al., 2019b]. The solution class for this problem revolves around the idea that the learned policy should be kept close to the data-generating process (or behavior policy), and has been given a variety of names (such as batch-constrained [Fujimoto et al., 2019b], KL-control [Jaques et al., 2019], behavior-regularized [Wu et al., 2019], or policy constraint [Levine et al., 2020]) depending on how this “closeness” is chosen to be implemented.

While there are many proposed approaches to offline RL, we remark that few are truly “simple”, and even the algorithms which claim to work with minor additions to an underlying online RL
algorithm make a significant number of implementation-level adjustments. In other cases, there are unmentioned hyperparameters, or secondary components, such as generative models, which make offline RL algorithms difficult to reproduce, and even more challenging to tune. Additionally, such mixture of details slow down the run times of the algorithms, and make causal attributions of performance gains and transfers of techniques across algorithms difficult, as in the case for many online RL algorithms [Henderson et al., 2017, Tucker et al., 2018, Engstrom et al., 2020, Andrychowicz et al., 2021, Furuta et al., 2021]. This motivates the need for more minimalist approaches in offline RL.

In this paper, we ask: can we make a deep RL algorithm work offline with minimal changes? We find that we can match the performance of state-of-the-art offline RL algorithms with a single adjustment to the policy update step of the TD3 algorithm [Fujimoto et al., 2018]. TD3’s policy $\pi$ is updated with the deterministic policy gradient [Silver et al., 2014]:

$$\pi = \arg\max_{\pi} E_{(s,a) \sim D}[Q(s, \pi(s))].$$

Our proposed change, TD3+BC, is to simply add a behavior cloning term to regularize the policy:

$$\pi = \arg\max_{\pi} E_{(s,a) \sim D}[\lambda Q(s, \pi(s)) - (\pi(s) - a)^2],$$

with a single hyperparameter $\lambda$ to control the strength of the regularizer. This modification can be made by adjusting only a single line of code. Additionally, we remark that normalizing the states over the dataset, such that they have mean 0 and standard deviation 1, improves the stability of the learned policy. Importantly, these are the only changes made to the underlying deep RL algorithm. To accommodate reproducibility, all of our code is open-sourced.

We evaluate our minimal changes to the TD3 algorithm on the D4RL benchmark of continuous control tasks [Fu et al., 2020]. We find that our algorithm compares favorably against many offline RL algorithms, while being significantly easier to implement and more than halving the required computation cost. The surprising effectiveness of our minimalist approach suggests that in the context of offline RL, simpler approaches have been left underexplored in favor of more elaborate algorithmic contributions.

2 Related Work

Although to the best of our knowledge, we are the first to use TD3 with behavior cloning (BC) for the purpose of offline RL, we remark that combining RL with BC, and other imitation learning approaches, has been previously considered by many authors.

**RL + BC.** With the aim of accelerating reinforcement learning from examples (known as learning from demonstrations [Atkeson and Schaal, 1997]), BC has been used as a regularization for policy optimization with DDPG [Lillicrap et al., 2015] Nair et al., 2018, Goecks et al., 2020 and the natural policy gradient [Kakade, 2001, Rajeswaran et al., 2017], but with additional sophistication through modified replay buffers and pre-training. The most similar work to our own is a SAC+BC baseline [Haarnoja et al., 2018] from Nair et al. [2020] and an unpublished course project [Booher] combining PPO [Schulman et al., 2017] with BC.

**RL + Imitation.** Other than directly using BC with RL, imitation learning has been combined with RL in a variety of manners, such as mixed with adversarial methods [Zhu et al., 2018, Kang et al. 2018], used for pre-training [Pfeiffer et al., 2018], modifying the replay buffer [Vecerik et al., 2017, Gulcehre et al., 2020], adjusting the value function [Kim et al., 2013, Hester et al., 2017], or reward shaping [Judah et al., 2014, Wu et al., 2021]. In all cases, these methods use demonstrations as a method for overcoming challenges in exploration or improving the learning speed of the RL agent.

**Offline RL.** As aforementioned, offline RL methods generally rely on some approach for “staying close” to the data. This may be implemented using an estimate of the behavior policy and then defining an explicit policy parameterization [Fujimoto et al., 2019b, Ghasemipour et al., 2020] or by using divergence regularization [Jaques et al., 2019, Kumar et al., 2019, Wu et al., 2019, Siegel et al., 2020, Guo et al., 2021, Kostrikov et al., 2021]. Other approaches use a weighted version of BC to favor high advantage actions [Wang et al., 2018, Peng et al., 2019, Siegel et al., 2020, Wang et al.].
Some methods have modified the set of valid actions based on counts [Laroche et al., 2019] or the learned behavior policy [Fujimoto et al., 2019a]. Another direction is to implement divergence regularization as a form of pessimism into the value estimate [Nachum et al., 2019, Kumar et al., 2020, Buckman et al., 2020].

Meta Analyses of RL Algorithms. There are a substantial amount of meta analysis works on online RL algorithms. While some focus on inadequacies in the experimental protocols [Henderson et al., 2017, Osband et al., 2019], others study the roles of subtle implementation details in algorithms [Tucker et al., 2018, Engstrom et al., 2020, Andrychowicz et al., 2021, Furuta et al., 2021]. For example, Tucker et al. [2018], Engstrom et al. [2020] identified that superior performances of certain algorithms were more dependent on, or even accidentally due to, minor implementation rather than algorithmic differences. Furuta et al. [2021] study two broad families of off-policy algorithms, which most offline algorithms are based on, and find that a few subtle implementation details are strongly co-adapted and critical to specific algorithms, making attributions of performance gains difficult. Recent offline research also follows a similar trend, where a number of implementation modifications are necessary for high algorithmic performances (see Table 1). In contrast, we derive our algorithm by modifying the existing TD3 with only a few lines of codes. Our results suggest the community could also learn from careful explorations of simpler alternatives, besides emphasizing algorithmic novelties and complexities.

3 Background

RL. Reinforcement learning (RL) is a framework aimed to deal with tasks of sequential nature. Typically, the problem is defined by a Markov decision process (MDP) \((S, A, R, p, \gamma)\), with state space \(S\), action space \(A\), scalar reward function \(R\), transition dynamics \(p\), and discount factor \(\gamma\) [Sutton and Barto, 1998]. The behavior of an RL agent is determined by a policy \(\pi\) which maps states to actions (deterministic policy), or states to a probability distribution over actions (stochastic policy). The objective of an RL agent is to maximize the expected discounted return \(\mathbb{E}_\pi \left[ \sum_{t=0}^{\infty} \gamma^t r_{t+1} \right]\), which is the expected cumulative sum of rewards when following the policy in the MDP, where the importance of the horizon is determined by the discount factor. We measure this objective by a value function, which measures the expected discounted return after taking the action \(a\) in state \(s\):

\[
Q^\pi(s, a) = \mathbb{E}_\pi \left[ \sum_{t=0}^{\infty} \gamma^t r_{t+1} | s_0 = s, a_0 = a \right].
\]

BC. Another approach for training policies is through imitation of an expert or behavior policy. Behavior cloning (BC) is an approach for imitation learning [Pomerleau, 1991], where the policy is trained with supervised learning to directly imitate the actions of a provided dataset. Unlike RL, this process is highly dependent on the performance of the data-collecting process.

Offline RL. Offline RL breaks the assumption that the agent can interact with the environment. Instead, the agent is provided a fixed dataset which has been collected by some unknown data-generating process (such as a collection of behavior policies). This setting may be considered more challenging as the agent loses the opportunity to explore the MDP according to its current beliefs, and instead from infer good behavior from only the provided data.

One challenge for offline RL is the problem of extrapolation error [Fujimoto et al., 2019b], which is a generalization error in the approximate value function, induced by selecting actions not contained in the dataset. Simply put, it is difficult to evaluate the expected value of a policy which is sufficiently different from the behavior policy. Consequently, algorithms have taken the approach of constraining or regularizing the policy to stay near to the actions in the dataset [Levine et al., 2020].

4 Challenges in Offline RL

In this section, we identify key open challenges in offline RL通过 analyzing and evaluating prior algorithms. We believe these challenges highlight the importance of minimalist approaches, where performance can be easily attributed to algorithmic contributions, rather than entangled with the specifics of implementation.

Implementation and Tuning Complexities. RL algorithms are notoriously difficult to implement and tune [Henderson et al., 2017, Engstrom et al., 2020, Furuta et al., 2021], where minor code-level
Algorithmic Adjustments

Add regularizer to critic†
Approximate logsumexp with sampling‡

Train a generative model†‡
Replace critic with offset function
Gradient penalty on offset function‡

Add a BC term†

Implementation Adjustments

Architecture†‡
Actor learning rate†
Pre-training actor
Remove SAC entropy term
Max over sampled actions‡

Architecture†‡
Reward bonus†
Remove SAC entropy term

Normalize states

Table 1: Implementation changes offline RL algorithms make to the underlying base RL algorithm. † corresponds to details that add additional hyperparameter(s), and ‡ corresponds to ones that add a computational cost.

Figure 1: Percent difference of performance of offline RL algorithms and their simplified versions which remove implementation adjustments to their underlying algorithm. HC = HalfCheetah, Hop = Hopper, W = Walker, r = random, m = medium, mr = medium-replay, me = medium-expert, e = expert. Huge drops in performances show that the implementation complexities are crucial for achieving the best results in these prior algorithms.

Optimizations and hyperparameters can have non-trivial impact of performance and stability. This problem may be additionally amplified in the context of offline RL, where evaluating changes to implementation and hyperparameters is counter-intuitive to the nature of offline RL, which explicitly aims to eliminate environment interactions [Paine et al., 2020, Yang et al., 2020].

Most offline RL algorithms are built explicitly on top of an existing off-policy deep RL algorithm, such as TD3 [Fujimoto et al., 2018] or SAC [Haarnoja et al., 2018], but then further modify the underlying algorithm with "non-algorithmic" implementation changes, such as modifications to network architecture, learning rates, or pre-training the actor network. We remark that a desirable property of an offline RL algorithm would be to minimally modify the underlying algorithm, so as to reduce the space of possible adjustments required to achieve a strong performance.

In Table 1 we examine the particular modifications made by two recent offline RL algorithms, CQL [Kumar et al., 2020] and Fisher-BRC [Kostrikov et al., 2021]. On top of algorithmic changes, CQL also adds a pre-training phase where the actor is only trained with imitation learning and selects the max action over a sampled set of actions from the policy during evaluation. Fisher-BRC adds a constant reward bonus to every transition. Both methods modify SAC by removing the entropy term in the target update and modify the default network architecture. These changes add supplementary hyperparameters which may need to be tuned or increase computational costs.

In the online setting, these changes are relatively inconsequential and could be validated with some simple experimentation. However, in the offline setting, where we cannot interact with the environment, making additional adjustments to the underlying algorithm should be considered as more costly as validating their effectiveness is no longer a trivial additional step. This is also problematic because unlike the algorithmic changes proposed by these papers, these implementation details are not well justified, meaning there is much less intuition as to when to include these details, or how to adjust them with minimal experimentation. In the case of the D4RL benchmark on MuJoCo tasks [Todorov et al., 2012, Fu et al., 2020], we have a strong prior that our base deep RL algorithm performs well, as SAC/TD3 are considered state-of-the-art (or nearly) in these domains. If additional changes are necessary, then it suggests the algorithmic contributions alone are insufficient.
In Figure 1, we examine the percent difference in performance when removing the implementation changes in CQL and Fisher-BRC. There is a significant drop in performance in many of the tasks. This is not necessarily a death knell to these algorithms, as it is certainly possible these changes could be kept without tuning when attempting new datasets and domains. However, since neither paper make mention of a training/validation split, we can only assume these changes were made with their evaluation datasets in mind (D4RL, in this instance), and remark there is insufficient evidence that these changes may be universal. Ultimately, we make this point not to suggest a fundamental flaw with pre-existing algorithms, but to suggest that there should be a preference for making minimal adjustments to the underlying RL algorithm, to reduce the need for hyperparameter tuning.

**Extra Computation Requirement.** A secondary motivating factor for minimalism is avoiding the additional computational costs associated with modifying the underlying algorithm (in particular architecture) and more complex algorithmic ideas. In Table 3 (contained later in Section 6), we examine the run time of offline RL algorithms, as well as the change in cost over the underlying algorithm, and find their is a significant computational cost associated with these modifications. On top of the architecture changes, for CQL this is largely due to the costs of logsumexp over multiple sampled actions, and for Fisher-BRC, the costs associated with training the independent generative model. Since an objective of offline RL is to take advantage of existing, potentially large, datasets, there should be a preference for scalable and efficient solutions. Of course, run time should not come at the cost of performance, but as we will later demonstrate, there exists a simple, and computationally-free, approach for offline RL which matches the performance of current state-of-the-art algorithms.

**Instability of Trained Policies.** In analyzing the final trained policies of prior offline algorithms, we learned of a tangential, and open, challenge in the form of instability. In online RL, if the current policy is unsatisfactory, we can use checkpoints of previous iterations of the policy, or to simply continue training. However, in offline RL, the evaluation should only occur once by definition, greatly increasing the importance of the single policy at evaluation time. We highlight two versions of instability in offline RL. Figure 2 shows that in contrast to the online-trained policy, which converges to a robust low-variance policy, the offline-trained policy exhibits huge variances in performance.
during a single evaluation. Therefore, even if the average performance is reasonable, the agent may still perform poorly on some episodes. Figure 3 shows instability over the set of evaluations, which means the performance of the agent may be dependent on the specific stopping point chosen for evaluation. This questions the empirical effectiveness of offline RL for safety-critical real-world use cases [Mandel et al., 2014; Gottesman et al., 2018; Gauci et al., 2018; Jaques et al., 2019; Matsushima et al., 2020] as well as the current trend of reporting only the mean-value of the final policy in offline benchmarking [Pu et al., 2020].

Such variances are not likely caused by high policy entropies (e.g. TD3+BC trains a deterministic policy), but rather our hypothesis is that such a problem is due to distributional shifts issues and poor generalizations across unobserved states caused by offline nature of training [Ross et al., 2011], where the optimized policy is never allowed to execute in the environment, similarly as in BC. This trait of offline RL algorithms appears to be consistent across all offline algorithms we evaluated, even for our minimalistic TD3+BC that is only a few lines change from TD3. While we could not solve this challenge sufficiently within the scope of this work, the fact that this is reproducible even in the minimalistic variant proves that this a fundamental problem shared by all offline training settings, and is a critical problem for the community to study in the future.

5 A Minimalist Offline RL Algorithm

A key problem in offline RL, extrapolation error, can be summarized as the inability to properly evaluate out-of-distribution actions. Consequently, there has been a variety of different approaches to limiting, or regularizing, action selection such that the learned policy is easier to evaluate with the given dataset. We remark that while minimizing say, KL divergence, is a both logical and valid approach for reducing extrapolation error, there is no fundamental argument why minimizing one divergence or distance metric should be better than another. Thus, rather than derive an entirely new approach, we focus on simplicity, and present an offline RL algorithm which requires minimal modifications to a pre-existing deep RL algorithm. As discussed in Section 4 a minimalistic approach has a variety of benefits, such as reducing the number of hyperparameters to tune, increasing scalability by reducing computational costs, and providing an avenue for analyzing problems by disentangling algorithmic contributions from implementation details.

We now describe such an approach to offline RL. Our algorithm builds on top of TD3 [Fujimoto et al., 2018], making only two straightforward changes. Firstly, we add a behavior cloning regularization term to the standard policy update step of TD3, to push the policy towards favoring actions contained in the dataset $\mathcal{D}$:

$$\pi = \arg\max_{\pi} \mathbb{E}_{s \sim \mathcal{D}} [Q(s, \pi(s))] \rightarrow \pi = \arg\max_{\pi} \mathbb{E}_{(s, a) \sim \mathcal{D}} \left[ \lambda Q(s, \pi(s)) - (\pi(s) - a)^2 \right].$$  \hfill (3)

Secondly, we normalize the features of every state in the provided dataset. Let $s_i$ be the $i$th feature of the state $s$, let $\mu_i, \sigma_i$ be the mean and standard deviation, respectively, of the $i$th feature across the dataset:

$$s_i = \frac{s_i - \mu_i}{\sigma_i + \epsilon},$$  \hfill (4)

where $\epsilon$ is a small normalization constant (we use $10^{-3}$). While we remark this is a commonly used implementation detail in many deep RL algorithms [Raffin et al., 2019], we highlight it as (1) we want complete transparency about all implementation changes and (2) normalizing provides a non-trivial performance benefit in offline RL, where it is particularly well-suited as the dataset remains fixed.

While the choice of $\lambda$ in Equation (3) is ultimately just a hyperparameter, we observe that the balance between RL (in maximizing $Q$) and imitation (in minimizing the BC term), is highly susceptible to the scale of $Q$. If we assume an action range of $[-1, 1]$, the BC term is at most 4, however the range of $Q$ will be a function of the scale of the reward. Consequently, we can add a normalization term into $\lambda$. Given the dataset of $N$ transitions $(s_i, a_i)$, we define the scalar $\lambda$ as:

$$\lambda = \frac{\alpha}{\mathbb{E} \sum_{(s_i, a_i)} |Q(s_i, a_i)|}.$$  \hfill (5)

This is simply a normalization term based on the average absolute value of $Q$. In practice, we estimate this mean term over mini-batches, rather than the entire dataset. Although this term includes $Q$, it is
Table 2: Average normalized score over the final 10 evaluations and 5 seeds. The highest performing scores are highlighted. CQL and Fisher-BRC are re-run using author-provided implementations to ensure an identical evaluation process, while BRAC and AWAC use previously reported results. ± captures the standard deviation over seeds. TD3+BC achieves effectively the same performances as the state-of-the-art Fisher-BRC, despite being much simpler to implement and tune and more than halving the computation cost.

not differentiated over, and is simply used to scale the loss. This formulation has the added benefit of normalizing the learning rate across tasks, as the gradient $\nabla_a Q(s, a)$ will also be dependent on the scale of $Q$. We use $\alpha = 2.5$ in our experiments.

This completes the description of TD3+BC. The Equations (3), (4), and (5) summarizes the entirety of our changes to TD3, and can be implemented by modifying only a handful of lines in most codebases.

6 Experiments

We evaluate our proposed approach on the D4RL benchmark of OpenAI gym MuJoCo tasks [Todorov et al., 2012, Brockman et al., 2016, Fu et al., 2020], which encompasses a variety of dataset settings and domains. Our offline RL baselines include two state-of-the-art algorithms, CQL [Kumar et al., 2020] and Fisher-BRC [Kostrikov et al., 2021], as well as BRAC [Wu et al., 2019] and AWAC [Nair et al., 2020] due to their algorithmic simplicity.

To ensure a fair and identical experimental evaluation across algorithms, we re-run the state-of-the-art algorithms CQL and Fisher-BRC using the author-provided implementations\[23\]. We train each algorithm for 1 million time steps and evaluate every 5000 time steps. Each evaluation consists of 10 episodes. Results for BRAC are obtained from the D4RL benchmark and from the CQL paper, while the AWAC results are obtained directly from the paper. BC results were obtained using our own implementation.

D4RL. We report the final performance results in Table 2 and display the learning curves in Figure 4. Although our method is very simplistic in nature, it surpasses, or matches, the performance of the current state-of-the-art offline RL algorithms in most tasks. Only Fisher-BRC exhibits a comparable
Figure 4: Learning curves comparing the performance of TD3+BC against offline RL baselines in the D4RL datasets. Curves are averaged over 5 seeds, with the shaded area representing the standard deviation across seeds. TD3+BC exhibits a similar learning speed and final performance as the state-of-the-art Fisher-BRC, without the need of pre-training a generative model.

Table 3: Run time comparison of training each offline RL algorithm (does not include evaluation costs). (Left) Breakdown of the cost of the added implementation details (mainly architecture changes) and the algorithmic details by each method. (Right) Total training time of each algorithm. While CQL and Fisher-BRC have significantly increased computational costs over their base online RL algorithm due to various added complexities (e.g. see Table 1), TD3+BC has effectively no increase. This results in less than half of the computational cost of these prior state-of-the-art algorithms.

Run time. We evaluate run time of training each of the offline RL algorithms for 1 million time steps, using the author-provided implementations. Additionally, for fair comparison, we re-implement Fisher-BRC, allowing each method to be compared in the same framework (PyTorch [Paszke et al., 2019]). The results are reported in Table 3. Unsurprisingly, we find our approach compares favorably against previous methods in terms of wall-clock training time, effectively adding no cost to the underlying TD3 algorithm. All run time experiments were run with a single GeForce GTX 1080 GPU and an Intel Core i7-6700K CPU at 4.00GHz.

Ablation. In Figure 5, we perform an ablation study over the components in our method. As noted in previous work [Fujimoto et al., 2019b], without behavior cloning regularization, the RL algorithm alone is insufficient to achieve a high performance (except on some of the random data sets). We

As noted by previous papers [Kostrikov et al., 2021], we remark the author-provided implementation of CQL achieves a lower result than their reported results.
we hope to inspire future work to revisit simpler alternatives which may have been overlooked. Additionally, we highlight existing open challenges in offline RL research, including not only the value function is determined by $\alpha$ but note the performance on a subset of tasks begins to decrease as $\alpha$ sensitivity of the algorithm to the hyperparameter $\lambda$ the form of the sole hyperparameter $\alpha = \sum_{(s,a)} \alpha$ Q(s,a) on the value function is determined by $\alpha$. On many tasks, our approach is robust to this weighting factor, but note the performance on a subset of tasks begins to decrease as $\alpha$ begins to more heavily favor imitation ($\alpha = 1$) or RL ($\alpha = 4$).

7 Conclusion

Most recent advances in offline RL center around the idea of regularizing policy actions to be close to the support within batch data, and yet many state-of-the-art algorithms have significant complexities and additional modifications beyond base algorithms that lead to not only much slower run time, but also intractable attributions for sources of performance gains. Instead of complexity we optimize for extra implementation, computation, and hyperparameter-tuning complexities that we successfully address in this work, but also call attention to the neglected problem of high episodic variance in offline-trained policies compared to online-trained (see Figures 4 and 5) that we as the community should address in future works and benchmarking. Finally, we believe the sheer simplicity of our approach highlights a possible overemphasis on algorithmic complexity made by the community, and we hope to inspire future work to revisit simpler alternatives which may have been overlooked.
References

Martín Abadi, Ashish Agarwal, Paul Barham, Eugene Brevdo, Zhifeng Chen, Craig Citro, Greg S Corrado, Andy Davis, Jeffrey Dean, Matthieu Devin, et al. Tensorflow: Large-scale machine learning on heterogeneous distributed systems. arXiv preprint arXiv:1603.04467, 2016.

Marcin Andrychowicz, Anton Raichuk, Piotr Stańczyk, Manu Orsini, Sertan Girgin, Raphaël Marinier, Leonard Hussenot, Matthieu Geist, Olivier Pietquin, Marcin Michalski, Sylvain Gelly, and Olivier Bachem. What matters for on-policy deep actor-critic methods? a large-scale study. In International Conference on Learning Representations, 2021.

Christopher G Atkeson and Stefan Schaal. Robot learning from demonstration. In Proceedings of the Fourteenth International Conference on Machine Learning, pages 12–20, 1997.

Jonathan Booher. Bc+rl: Imitation learning from non-optimal demonstrations. URL https://web.stanford.edu/~jaustinb/papers/CS234.pdf.

Greg Brockman, Vicki Cheung, Ludwig Pettersson, Jonas Schneider, John Schulman, Jie Tang, and Wojciech Zaremba. Openai gym, 2016.

Jacob Buckman, Carles Gelada, and Marc G Bellemare. The importance of pessimism in fixed-dataset policy optimization. arXiv preprint arXiv:2009.06799, 2020.

Lili Chen, Kevin Lu, Aravind Rajeswaran, Kimin Lee, Aditya Grover, Michael Laskin, Pieter Abbeel, Aravind Srinivas, and Igor Mordatch. Decision transformer: Reinforcement learning via sequence modeling. arXiv preprint arXiv:2106.01345, 2021.

Xinyue Chen, Zijian Zhou, Zheng Wang, Che Wang, Yanqiu Wu, and Keith Ross. Bail: Best-action imitation learning for batch deep reinforcement learning. Advances in Neural Information Processing Systems, 33, 2020.

Logan Engstrom, Andrew Ilyas, Shibani Santurkar, Dimitris Tsipras, Firdaus Janoos, Larry Rudolph, and Aleksander Madry. Implementation matters in deep rl: A case study on ppo and trpo. In International Conference on Learning Representations, 2020.

Justin Fu, Aviral Kumar, Ofir Nachum, George Tucker, and Sergey Levine. D4rl: Datasets for deep data-driven reinforcement learning. 2020.

Scott Fujimoto, Herke van Hoof, and David Meger. Addressing function approximation error in actor-critic methods. In International Conference on Machine Learning, volume 80, pages 1587–1596. PMLR, 2018.

Scott Fujimoto, Edoardo Conti, Mohammad Ghavamzadeh, and Joelle Pineau. Benchmarking batch deep reinforcement learning algorithms. arXiv preprint arXiv:1910.01708, 2019a.

Scott Fujimoto, David Meger, and Doina Precup. Off-policy deep reinforcement learning without exploration. In International Conference on Machine Learning, pages 2052–2062, 2019b.

Hiroki Furuta, Tadashi Kozuno, Tatsuya Matsushima, Yutaka Matsuo, and Shixiang Shane Gu. Identifying co-adaptation of algorithmic and implementational innovations in deep reinforcement learning: A taxonomy and case study of inference-based algorithms. arXiv preprint arXiv:2103.17258, 2021.

Jason Gauci, Edoardo Conti, Yitaow Liang, Kittipat Virochsiri, Yuchen He, Zachary Kaden, Vivek Narayanan, Xiaohui Ye, Zhengxing Chen, and Scott Fujimoto. Horizon: Facebook’s open source applied reinforcement learning platform. arXiv preprint arXiv:1811.00260, 2018.

Seyed Kamyar Seyed Ghasempour, Dale Schuurmans, and Shixiang Shane Gu. Emaq: Expected-max q-learning operator for simple yet effective offline and online rl. arXiv preprint arXiv:2007.11091, 2020.

Vinicius G Goecks, Gregory M Gremlillion, Vernon J Lawhern, John Valasek, and Nicholas R Waytowich. Integrating behavior cloning and reinforcement learning for improved performance in dense and sparse reward environments. In Proceedings of the 19th International Conference on Autonomous Agents and MultiAgent Systems, pages 465–473, 2020.
Omer Gottesman, Fredrik Johansson, Joshua Meier, Jack Dent, Donghun Lee, Srivatsan Srinivasan, Linying Zhang, Yi Ding, David Wihl, Xuefeng Peng, et al. Evaluating reinforcement learning algorithms in observational health settings. *arXiv preprint arXiv:1805.12298*, 2018.

Caglar Gulcehre, Tom Le Paine, Bobak Shahriari, Misha Denil, Matt Hoffman, Hubert Soyer, Richard Tanburn, Steven Kapturowski, Neil Rabinowitz, Duncan Williams, Gabriel Barth-Maron, Ziyu Wang, Nando de Freitas, and Worlds Team. Making efficient use of demonstrations to solve hard exploration problems. In *International Conference on Learning Representations*, 2020.

Yijie Guo, Shengyu Feng, Nicolas Le Roux, Ed Chi, Honglak Lee, and Minmin Chen. Batch reinforcement learning through continuation method. In *International Conference on Learning Representations*, 2021.

Tuomas Haarnoja, Aurick Zhou, Pieter Abbeel, and Sergey Levine. Soft actor-critic: Off-policy maximum entropy deep reinforcement learning with a stochastic actor. In *International Conference on Machine Learning*, volume 80, pages 1861–1870. PMLR, 2018.

Peter Henderson, Riashat Islam, Philip Bachman, Joelle Pineau, Doina Precup, and David Meger. Deep reinforcement learning that matters. In *AAAI Conference on Artificial Intelligence*, 2017.

Todd Hester, Matej Vecerik, Olivier Pietquin, Marc Lanctot, Tom Schaul, Bilal Piot, Dan Horgan, John Quan, Andrew Sendonaris, Gabriel Dulac-Arnold, et al. Deep q-learning from demonstrations. *arXiv preprint arXiv:1704.03732*, 2017.

Natasha Jaques, Asma Ghandeharioun, Judy Hanwen Shen, Craig Ferguson, Agata Lapedriza, Noah Jones, Shixiang Gu, and Rosalind Picard. Way off-policy batch deep reinforcement learning of implicit human preferences in dialog. *arXiv preprint arXiv:1907.00456*, 2019.

Kshitij Judah, Alan Fern, Prasad Tadepalli, and Robby Goetschalckx. Imitation learning with demonstrations and shaping rewards. In *Proceedings of the AAAI Conference on Artificial Intelligence*, volume 28, 2014.

Sham Kakade. A natural policy gradient. In *Proceedings of the 14th International Conference on Neural Information Processing Systems: Natural and Synthetic*, pages 1531–1538, 2001.

Bingyi Kang, Zequn Jie, and Jiashi Feng. Policy optimization with demonstrations. In *International Conference on Machine Learning*, pages 2469–2478. PMLR, 2018.

Beomjoon Kim, Amir-massoud Farahmand, Joelle Pineau, and Doina Precup. Learning from limited demonstrations. In *Advances in Neural Information Processing Systems*, pages 2859–2867, 2013.

Diederik Kingma and Jimmy Ba. Adam: A method for stochastic optimization. *arXiv preprint arXiv:1412.6980*, 2014.

Ilya Kostrikov, Jonathan Tompson, Rob Fergus, and Ofir Nachum. Offline reinforcement learning with fisher divergence critic regularization. *arXiv preprint arXiv:2103.08050*, 2021.

Aviral Kumar, Justin Fu, Matthew Soh, George Tucker, and Sergey Levine. Stabilizing off-policy q-learning via bootstrapping error reduction. In *Advances in Neural Information Processing Systems*, pages 11784–11794, 2019.

Aviral Kumar, Aurick Zhou, George Tucker, and Sergey Levine. Conservative q-learning for offline reinforcement learning. *arXiv preprint arXiv:2006.04779*, 2020.

Sascha Lange, Thomas Gabel, and Martin Riedmiller. Batch reinforcement learning. In *Reinforcement Learning*, pages 45–73. Springer, 2012.

Romain Laroche, Paul Tricheltair, and Remi Tachet Des Combes. Safe policy improvement with baseline bootstrapping. In *International Conference on Machine Learning*, pages 3652–3661. PMLR, 2019.

Sergey Levine, Aviral Kumar, George Tucker, and Justin Fu. Offline reinforcement learning: Tutorial, review, and perspectives on open problems. *arXiv preprint arXiv:2005.01643*, 2020.
Timothy P Lillicrap, Jonathan J Hunt, Alexander Pritzel, Nicolas Heess, Tom Erez, Yuval Tassa, David Silver, and Daan Wierstra. Continuous control with deep reinforcement learning. *arXiv preprint arXiv:1509.02971*, 2015.

Travis Mandel, Yun-En Liu, Sergey Levine, Emma Brunskill, and Zoran Popovic. Offline policy evaluation across representations with applications to educational games. In *International Conference on Autonomous Agents and Multiagent Systems*, 2014.

Tatsuya Matsushima, Hiroki Furuta, Yutaka Matsuo, Ofir Nachum, and Shixiang Gu. Deployment-efficient reinforcement learning via model-based offline optimization. *arXiv preprint arXiv:2006.03647*, 2020.

Ofir Nachum, Bo Dai, Ilya Kostrikov, Yinlam Chow, Lihong Li, and Dale Schuurmans. Algaedice: Policy gradient from arbitrary experience. *arXiv preprint arXiv:1912.02074*, 2019.

Ashvin Nair, Bob McGrew, Marcin Andrychowicz, Wojciech Zaremba, and Pieter Abbeel. Overcoming exploration in reinforcement learning with demonstrations. In *2018 IEEE International Conference on Robotics and Automation (ICRA)*, pages 6292–6299. IEEE, 2018.

Ashvin Nair, Murtaza Dalal, Abhishek Gupta, and Sergey Levine. Accelerating online reinforcement learning with offline datasets. *arXiv preprint arXiv:2006.09359*, 2020.

Ian Osband, Yotam Doron, Matteo Hessel, John Aslanides, Eren Sezener, Andre Saraiva, Katrina McKinney, Tor Lattimore, Csaba Szepesvari, Satinder Singh, et al. Behaviour suite for reinforcement learning. *arXiv preprint arXiv:1908.03568*, 2019.

Tom Le Paine, Cosmin Paduraru, Andrea Michi, Caglar Gulcehre, Konrad Zolna, Alexander Novikov, Ziyu Wang, and Nando de Freitas. Hyperparameter selection for offline reinforcement learning. *arXiv preprint arXiv:2007.09055*, 2020.

Adam Paszke, Sam Gross, Francisco Massa, Adam Lerer, James Bradbury, Gregory Chanan, Trevor Killeen, Zeming Lin, Natalia Gimelshein, Luca Antiga, et al. Pytorch: An imperative style, high-performance deep learning library. In *Advances in Neural Information Processing Systems*, pages 8024–8035, 2019.

Xue Bin Peng, Aviral Kumar, Grace Zhang, and Sergey Levine. Advantage-weighted regression: Simple and scalable off-policy reinforcement learning. *arXiv preprint arXiv:1910.00177*, 2019.

Mark Pfeiffer, Samarth Shukla, Matteo Turchetta, Cesar Cadena, Andreas Krause, Roland Siegwart, and Juan Nieto. Reinforced imitation: Sample efficient deep reinforcement learning for mapless navigation by leveraging prior demonstrations. *IEEE Robotics and Automation Letters*, 3(4): 4423–4430, 2018.

Dean A Pomerleau. Efficient training of artificial neural networks for autonomous navigation. *Neural computation*, 3(1):88–97, 1991.

Antonin Raffin, Ashley Hill, Maximilian Ernestus, Adam Gleave, Anssi Kanervisto, and Noah Dormann. Stable baselines3, [https://github.com/DLR-RAI/stable-baselines3](https://github.com/DLR-RAI/stable-baselines3) 2019.

Aravind Rajeswaran, Vikash Kumar, Abhishek Gupta, Giulia Vezzani, John Schulman, Emanuel Todorov, and Sergey Levine. Learning complex dexterous manipulation with deep reinforcement learning and demonstrations. *arXiv preprint arXiv:1709.10087*, 2017.

Stéphane Ross, Geoffrey Gordon, and Drew Bagnell. A reduction of imitation learning and structured prediction to no-regret online learning. In *Proceedings of the fourteenth international conference on artificial intelligence and statistics*, pages 627–635. JMLR Workshop and Conference Proceedings, 2011.

John Schulman, Filip Wolski, Prafulla Dhariwal, Alec Radford, and Oleg Klimov. Proximal policy optimization algorithms. *arXiv preprint arXiv:1707.06347*, 2017.

Noah Siegel, Jost Tobias Springenberg, Felix Berkenkamp, Abbas Abdolmaleki, Michael Neunert, Thomas Lampe, Roland Hafner, Nicolas Heess, and Martin Riedmiller. Keep doing what worked: Behavior modelling priors for offline reinforcement learning. In *International Conference on Learning Representations*, 2020.
David Silver, Guy Lever, Nicolas Heess, Thomas Degris, Daan Wierstra, and Martin Riedmiller. Deterministic policy gradient algorithms. In *International Conference on Machine Learning*, pages 387–395, 2014.

Richard S Sutton and Andrew G Barto. *Reinforcement learning: An introduction*, volume 1. MIT press Cambridge, 1998.

Emanuel Todorov, Tom Erez, and Yuval Tassa. Mujoco: A physics engine for model-based control. In *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pages 5026–5033. IEEE, 2012.

George Tucker, Surya Bhupatiraju, Shixiang Gu, Richard Turner, Zoubin Ghahramani, and Sergey Levine. The mirage of action-dependent baselines in reinforcement learning. In *International Conference on Machine Learning*, 2018.

Matej Večerík, Todd Hester, Jonathan Scholz, Fumin Wang, Olivier Pietquin, Bilal Piot, Nicolas Heess, Thomas Rothörl, Thomas Lampe, and Martin Riedmiller. Leveraging demonstrations for deep reinforcement learning on robotics problems with sparse rewards. *arXiv preprint arXiv:1707.08817*, 2017.

Qing Wang, Jiechao Xiong, Lei Han, Peng Sun, Han Liu, and Tong Zhang. Exponentially weighted imitation learning for batched historical data. In *Proceedings of the 32nd International Conference on Neural Information Processing Systems*, pages 6291–6300, 2018.

Ziyu Wang, Alexander Novikov, Konrad Zolna, Josh S Merel, Jost Tobias Springenberg, Scott E Reed, Bobak Shahriari, Noah Siegel, Caglar Gulcehre, Nicolas Heess, et al. Critic regularized regression. *Advances in Neural Information Processing Systems*, 33, 2020.

Yifan Wu, George Tucker, and Ofir Nachum. Behavior regularized offline reinforcement learning. *arXiv preprint arXiv:1911.11361*, 2019.

Yuchen Wu, Melissa Mozifian, and Florian Shkurti. Shaping rewards for reinforcement learning with imperfect demonstrations using generative models. In *2021 IEEE International Conference on Robotics and Automation (ICRA)*, pages 6628–6634. IEEE, 2021.

Mengjiao Yang, Bo Dai, Ofir Nachum, George Tucker, and Dale Schuurmans. Offline policy selection under uncertainty. *arXiv preprint arXiv:2012.06919*, 2020.

Yuke Zhu, Ziyu Wang, Josh Merel, Andrei Rusu, Tom Erez, Serkan Cabi, Saran Tunyasuvunakool, János Kramár, Raia Hadsell, Nando de Freitas, et al. Reinforcement and imitation learning for diverse visuomotor skills. *arXiv preprint arXiv:1802.09564*, 2018.
A Broader Impact

Offline RL will have societal impact by enabling new applications for reinforcement learning which can benefit from offline logged data such as robotics or healthcare applications, where collecting data is difficult, time-gated, expensive, etc. This may include potentially negative applications such as enforcing addictive behavior on social media. Another limitation to offline RL is that it is subject to any biases contained in the data set and can influenced by the data-generating policy.

For our specific algorithm, TD3+BC, given the performance gain over existing state-of-the-art methods is minimal, it would be surprising to see our paper result in significant impact in these contexts. However, where we might see impact is in enabling new users access to offline RL by reducing the computational cost, or burden of implementation, from having a simpler approach to offline RL. In other words, we foresee the impact our work is in accessibility and ease-of-use, and not through changing the scope of possible applications.

B Experimental Details

Software. We use the following software versions:

- Python 3.6
- Pytorch 1.4.0 [Paszke et al., 2019]
- Tensorflow 2.4.0 [Abadi et al., 2016]
- Gym 0.17.0 [Brockman et al., 2016]
- MuJoCo 1.5 [Todorov et al., 2012]
- mujoco-py 1.50.1.1

All D4RL datasets [Fu et al., 2020] use the v0 version.

Hyperparameters. Our implementations of TD3 [Fujimoto et al., 2018], CQL [Kumar et al., 2020], and Fisher-BRC [Kostrikov et al., 2021] are based off of their respective author-provided implementations from GitHub. For TD3+BC, only $\alpha$ was tuned in the range $(1, 2, 2.5, 3, 4)$ on Hopper-medium-v0 and Hopper-expert-v0 on a single seed which was unused in final reported results. We use default hyperparameters according to each GitHub whenever possible. For CQL we modify the GitHub defaults for the actor learning rate and use a fixed $\alpha$ rather than the Lagrange variant, matching the hyperparameters defined in their paper (which differs from the GitHub), as we found the original hyperparameters performed better. Our re-implementation of Fisher-BRC (in PyTorch rather than Tensorflow) is used only for run time experiments.

We outline the hyperparameters used by TD3+BC in Table 4, CQL in Table 5, and Fisher-BRC in Table 6.

Heuristics for selecting $\lambda$. While we find a single setting of $\lambda$ works across all datasets, some practitioners may be interested in guidelines in choosing $\lambda$, such as setting it to a fixed constant. Note the aim in our heuristic of normalizing by the average absolute value is to balance the importance of value maximization and behavior cloning. With domain knowledge, this heuristic can be circumvented by selecting $\lambda$ roughly equal to $\alpha$ over the expected average value. We can also choose $\lambda$ by considering the value estimate of the agent– if we see divergence in the value function due to extrapolation error [Fujimoto et al., 2019b], then we need to decrease $\lambda$ such that the BC term is weighted more highly. Alternatively, if the performance resembles the performance of the behavior agent, then higher values of $\lambda$ should be considered.

License information:

- https://www.roboti.us/license.html
- https://github.com/sfujim/TD3 commit 6a9f76101058d674518018fb532f5a652c1d37
- https://github.com/aviralkumar2907/CQL commit d67dbec9cf5d2b96c3b62b6146f249b3598986e602a/9872/ca8f413dbf8ae3c4ec48d0c0
| Hyperparameter                        | Value                        |
|--------------------------------------|------------------------------|
| Optimizer                            | Adam [Kingma and Ba, 2014]   |
| Critic learning rate                 | 3e-4                         |
| Actor learning rate                  | 3e-4                         |
| Mini-batch size                      | 256                          |
| Discount factor                      | 0.99                         |
| Target update rate                   | 5e-3                         |
| Policy noise                         | 0.2                          |
| Policy noise clipping                | (-0.5, 0.5)                  |
| Policy update frequency              | 2                            |
| Critic hidden dim                    | 256                          |
| Critic hidden layers                 | 2                            |
| Critic activation function           | ReLU                         |
| Actor hidden dim                     | 256                          |
| Actor hidden layers                  | 2                            |
| Actor activation function            | ReLU                         |

| Hyperparameter                        | Value                        |
|--------------------------------------|------------------------------|
| α                                     | 2.5                          |

Table 4: TD3+BC Hyperparameters. Recall the form of $\lambda = \frac{\alpha}{\sum_{(s,a)} (Q(s,a))}$. The hyperparameters of TD3 are not modified from the TD3 GitHub.

| Hyperparameter                        | Value                        |
|--------------------------------------|------------------------------|
| Optimizer                            | Adam [Kingma and Ba, 2014]   |
| Critic learning rate                 | 3e-4                         |
| Actor learning rate                  | 3e-5                         |
| Mini-batch size                      | 256                          |
| Discount factor                      | 0.99                         |
| Target update rate                   | 5e-3                         |
| Target entropy                       | -1 · Action Dim              |
| Entropy in Q target                  | False                        |
| Critic hidden dim                    | 256                          |
| Critic hidden layers                 | 3                            |
| Critic activation function           | ReLU                         |
| Actor hidden dim                     | 256                          |
| Actor hidden layers                  | 3                            |
| Actor activation function            | ReLU                         |

| Hyperparameter                        | Value                        |
|--------------------------------------|------------------------------|
| Lagrange                             | False                        |
| α                                     | 10                           |

Table 5: CQL Hyperparameters. We use the hyperparameters defined in the CQL paper rather than the default settings in the CQL GitHub as we found those settings performed poorly. ¹ denotes hyperparameters which deviate from the original SAC hyperparameters.
| Hyperparameter                        | Value                                    |
|--------------------------------------|------------------------------------------|
| **SAC Hyperparameters**              |                                          |
| Optimizer                            | Adam [Kingma and Ba 2014]                |
| Critic Learning Rate                 | 3e-4                                     |
| Actor Learning Rate                  | 3e-4                                     |
| Mini-batch size                      | 256                                      |
| Discount factor                      | 0.99                                     |
| Target update rate                   | 5e-3                                     |
| Target entropy                       | -1 · Action Dim                          |
| Entropy in Q target                  | False†                                   |
| **Architecture**                     |                                          |
| Critic hidden dim                    | 256                                      |
| Critic hidden layers                 | 3†                                       |
| Critic activation function           | ReLU                                     |
| Actor hidden dim                     | 256                                      |
| Actor hidden layers                  | 3†                                       |
| Actor activation function            | ReLU                                     |
| **Generative Model Hyperparameters** |                                          |
| Num Gaussians                        | 5                                        |
| Optimizer                            | Adam [Kingma and Ba 2014]                |
| Learning rate                        | (1e-3, 1e-4, 1e-5)                       |
| Learning rate schedule               | Piecewise linear (0, 8e5, 9e5)           |
| Target entropy                       | -1 · Action Dim                          |
| **Generative Model Architecture**    |                                          |
| Hidden dim                           | 256                                      |
| Hidden layers                        | 2                                        |
| Activation function                  | ReLU                                     |
| **Fisher-BRC Hyperparameters**       |                                          |
| Gradient penalty λ                   | 0.1                                      |
| Reward bonus                         | 5                                        |

Table 6: Fisher-BRC Hyperparameters. We use the default hyperparameters in the Fisher-BRC GitHub. † denotes hyperparameters which deviate from the original SAC hyperparameters.
C Additional Experiments

C.1 Additional Datasets

A concern of TD3+BC is the poor performance on random data. In Table 7 we mix the random and expert datasets from D4RL [Fu et al., 2020], by randomly selecting half the transitions from each dataset and concatenating. We find that TD3+BC performs comparatively to Fisher-BRC. However, both algorithms underperform CQL on Walker2d. One hypothesis for this performance gap is due to the poor performance of BC on the Walker2d expert dataset (see Table 2 and Figure 4 in the main body). For completeness we also report the performance of TD3+BC on the D4RL AntMaze datasets. For this domain we found that state feature normalization was harmful to performance and was not included. All other hyperparameters remain unchanged.

|                | CQL     | Fisher-BRC | TD3+BC  |
|----------------|---------|------------|---------|
| HalfCheetah    | 73.3±6.9| 105.8±2.5  | 101.9±7.6|
| Hopper         | 110.8±2.4| 111.9±0.9  | 112.2±0.3|
| Walker2d       | 100.3±8.5| 32.0±37.3  | 28.8±23.4|

Table 7: Average normalized score over the final 10 evaluations and 5 seeds on a mixture of 50% of the random D4RL dataset and 50% of the expert D4RL dataset. CQL and Fisher-BRC are re-run using author-provided implementations to ensure an identical evaluation process. ± captures the standard deviation over seeds.

|                | TD3+BC  |
|----------------|---------|
| AntMaze-Umaze  | 78.6±33.3|
| AntMaze-Umaze-Diverse | 71.4±20.7|
| AntMaze-Medium-Diverse | 10.6±10.1|
| AntMaze-Medium-Play   | 3.0±4.8 |
| AntMaze-Large-Diverse  | 0.2±0.4 |
| AntMaze-Large-Play     | 0.0±0.0 |

Table 8: Average normalized score over the final 10 evaluations and 5 seeds on the AntMaze environments. ± captures the standard deviation over seeds.

C.2 State Feature Normalization with Other Algorithms

To better understand the effectiveness of state feature normalization, we apply it to both CQL and Fisher-BRC. We report the percent difference of including this technique in Figure 7. We find that this generally has minimal impact on performance.

Figure 7: Percent difference of performance of offline RL algorithms when adding normalization to state features. HC = HalfCheetah, Hop = Hopper, W = Walker, r = random, m = medium, mr = medium-replay, me = medium-expert, e = expert.
C.3 Benchmarking against the Decision Transformer

The Decision Transformer (DT) is concurrent work which examines the use of the transformer architecture in offline RL, by framing the problem as sequence modeling [Chen et al., 2021]. The authors use the D4RL -v2 datasets, which non-trivially affects performance and make direct comparison to results on the -v0 datasets inaccurate. To compare against this approach, we re-run TD3+BC on the -v2 datasets. Results are reported in Table 9. Although DT uses state of the art techniques from language modeling, and some per-environment hyperparameters, we find TD3+BC achieves a similar performance without any additional hyperparameter tuning. Furthermore, we benchmark the training time of DT against TD3+BC, using the author-provided implementation in Figure 8, using the same experimental setup; a single GeForce GTX 1080 GPU and an Intel Core i7-6700K CPU at 4.00GHz. Unsurprisingly, TD3+BC trains significantly faster as it does not rely on the expensive transformer architecture.

| Dataset     | Environment | DT     | TD3+BC  |
|-------------|-------------|--------|---------|
| Random      | HalfCheetah  | 11.0 ± 1.1 | 42.6 ± 0.1 |
|             | Hopper      | 8.5 ± 0.6  | 67.6 ± 1 |
|             | Walker2d    | 1.6 ± 1.7  | 74.0 ± 1.4 |
| Medium      | HalfCheetah  | 42.6 ± 0.1 | 48.3 ± 0.3 |
|             | Hopper      | 67.6 ± 1  | 59.3 ± 4.2 |
|             | Walker2d    | 1.6 ± 1.7 | 83.7 ± 2.1 |
| Medium-Replay | HalfCheetah | 36.6 ± 0.8 | 44.6 ± 0.5 |
|              | Hopper      | 82.7 ± 7  | 60.9 ± 18.8 |
|              | Walker2d    | 66.6 ± 3  | 81.8 ± 5.5 |
| Medium-Expert | HalfCheetah | 86.8 ± 1.3 | 90.7 ± 4.3 |
|              | Hopper      | 107.6 ± 1.8 | 98.0 ± 9.4 |
|              | Walker2d    | 108.1 ± 0.2 | 110.1 ± 0.5 |
| Expert      | HalfCheetah  | -       | 96.7 ± 1.1 |
|             | Hopper      | -       | 107.8 ± 7 |
|             | Walker2d    | -       | 110.2 ± 0.3 |
| Total (DT)  |             | 672.6 ± 16.6 | 677.4 ± 45.6 |
| Total       |             | -       | 1013.2 ± 57.4 |

Table 9: Average normalized score using the D4RL -v2 datasets. The highest performing scores are highlighted. ± captures the standard deviation over seeds. Total (DT) sums scores over the subset of tasks with DT results. TD3+BC results are taken following the same experimental procedure as the -v0 datasets, averaging over the final 10 evaluations and 5 seeds. No additional hyperparameter tuning was performed. DT results are taken directly from the paper and uses 3 seeds. TD3+BC and DT achieve a comparable performance.

[https://github.com/kzl/decision-transformer](https://github.com/kzl/decision-transformer), commit 5fc73c19f1a89cb17e83aa656b6bba1986e9da59
Figure 8: Benchmarking wall-clock training time of DT and TD3+BC over 1 million steps. Does not include evaluation costs. We remark that the DT was trained with only 100k time steps, which reduces the computational cost substantially, but even with this reduction, the DT takes over twice as long as TD3+BC to train. For many of the D4RL tasks the performance of TD3+BC converges before 100k time steps (see the learning curves in Figure 4), but unlike the DT, we can let TD3+BC run for the full 1 million steps without incurring significant computational costs.