

Large Language Models as Efficient Reward Function Searchers for Custom-Environment Multi-Objective Reinforcement Learning

Guanwen Xie*, Jingzhe Xu*, Yiyuan Yang[†], Yimian Ding*, Shuai Zhang[‡]

*MicroMasters Program in Statistics and Data Science, Massachusetts Institute of Technology, USA

[†]Department of Computer Science, University of Oxford, United Kingdom

[‡]Department of Data Science, New Jersey Institute of Technology, USA

Email: sz457@njit.edu

Abstract—Achieving the effective design and improvement of reward functions in reinforcement learning (RL) tasks with complex custom environments and multiple requirements presents considerable challenges. In this paper, we propose ERFSL, an efficient reward function searcher using LLMs, which enables LLMs to be effective white-box searchers and highlights their advanced semantic understanding capabilities. Specifically, we generate reward components for each numerically explicit user requirement and employ a reward critic to identify the correct code form. Then, LLMs assign weights to the reward components to balance their values and iteratively adjust the weights without ambiguity and redundant adjustments by flexibly adopting directional mutation and crossover strategies, similar to genetic algorithms, based on the context provided by the training log analyzer. We applied the framework to an underwater data collection RL task without direct human feedback or reward examples (zero-shot learning). The reward critic successfully corrects the reward code with only one feedback instance for each requirement, effectively preventing unrectifiable errors. The initialization of weights enables the acquisition of different reward functions within the Pareto solution set without the need for weight search. Even in cases where a weight is 500 times off, on average, only 5.2 iterations are needed to meet user requirements. The ERFSL also works well with most prompts utilizing GPT-4o mini, as we decompose the weight searching process to reduce the requirement for numerical and long-context understanding capabilities¹.

Index Terms—Large language models, Multi-objective reinforcement learning, Reward function design

I. INTRODUCTION

Reinforcement learning (RL) methods are being increasingly utilized for intricate, multi-objective tasks. Nonetheless, as the variety and quantity of requirements and optimization goals grow, the design of reward functions becomes more complex, necessitating significant effort to adjust the structure and coefficients of each reward component. This complexity is further compounded by the fact that researchers’ needs often fluctuate with different scenarios and over time, and can sometimes be ambiguous [1], thereby posing a considerable challenge to achieving optimal performance.

Large language models (LLMs) are trained on extensive text data [2], enabling them to demonstrate strong problem-solving and content generation abilities when given well-written prompts, even without prior domain knowledge. The application of LLMs in creating functional code has shown remarkable performance across various tasks, such as dexterous robots control [3]–[5] and Minecraft playing [6], [7], highlighting their potential in zero-shot scenarios with limited self-evolution iterations. However, this improvement process depends on trial-and-error exploration. When there is a single, clear objective (e.g., success rate), the search space for designing functions and tuning parameters is confined, allowing for gradual optimization through iterations. However, for complex reward functions, where reward components and their weights are determined simultaneously, issues such as incorrect code and imbalanced weights may arise, which are difficult to resolve solely through training feedback. To address these challenges, some approaches decompose complex tasks into several sub-tasks or skills, while providing clear task feedback accordingly [8]–[10].

Furthermore, multi-objective RL tasks face the challenge of balancing the weights and values in the reward function. A related topic is LLM-driven white-box numerical optimization [2], [11], [12], such as hyperparameter optimization (HPO) [11], [13]. This approach involves abstracting all explicitly defined coefficients and the function code itself into parameters, allowing LLMs to perform comprehensive analyses and improvements on well-defined machine learning tasks. This paradigm aligns with the observation that LLMs are particularly adept at summarizing and heuristically generating code within specific and clear task contexts, yet they are less proficient in addressing black-box optimization problems [14].

These considerations underscore the necessity of providing clear task descriptions while rationally exploring the extensive search space. We propose ERFSL, an efficient reward function searcher via LLMs for custom-environment multi-objective RL, which utilizes task decomposition and white-box search to fully leverage LLMs’ semantic understanding capabilities. Unlike previous work, we separate the reward-generating process into reward code design and reward weight searching,

¹ The full-text prompts, examples of LLM-generated answers, and source code are available at <https://360zmem.github.io/LLMRsearcher/>.

weights to ensure these components’ values are on the same scale. This approach prevents the initial weight groups from deviating significantly from the optimal solutions. Afterward, the reward weight searcher offers new weight solutions based on the training results. Existing methods utilize Python list-style training logs to present these results. However, detailed logs make the prompt excessively lengthy and complex, significantly hindering textual and numerical understanding, especially for small-scale LLMs [16], [17]. Consequently, we employ a training log analyzer to produce a concise textual summary of the task.

To facilitate directional adjustment and minimize the impact of errors in LLM decision-making, the reward weight searcher processes $K=5$ input weight groups and generates $K=5$ output groups. The reward weight initializer designates the first weight group as the starting point for the search, with the other four sets subsequently adjusting certain weights of the first set. Subsequently, the reward weight searcher provides suggestions for weight adjustment based on training results summarized by the training log analyzer. To prevent ambiguity and potential redundancies in weight adjustments across multiple input sets, the searcher specifies starting points for mutation (adjustment) on each weight from a certain input group, allowing for directional modifications like maintaining, increasing/decreasing, or fine-tuning weights. For multiple weight adjustments, we conduct crossovers between the modified weight groups to integrate changes made in mutated input groups relative to the search start point. While borrowing the terminologies from the genetic algorithm and inspired by it, our process ensures directed mutation based on input groups and selective crossovers to enhance search efficiency.

The complex search strategies arising from multiple weight groups lead to lengthy prompts. Similarly, by separating the processes of generating adjustment suggestions and new output weight groups, we ensure the necessary understanding for the former and precise execution for the latter.

III. EXPERIMENTS

A. Task Description and Parameters

To evaluate the proposed ERFSL framework, we select the underwater data collection task from our previous work [15], which utilizes the RL algorithm to control multiple autonomous underwater vehicles (AUVs) for data collection. We task LLMs with designing reward functions encompassing safety requirements (collision and border crossing avoidance), performance requirements (timely serving of the target SN to minimize data overflow), and performance objectives (reduce energy consumption), without providing any reward examples (namely zero-shot), as shown in the task description in Fig. 1. We refer to the original paper for the system models and simulation parameters. For determinacy, TD3 [18] is used as the RL algorithm instead of MAISAC, as in the original paper.

For experiments, we utilize `gpt-4o-2024-08-06` (denoted as **GPT-4o**) as the default LLM due to its improved performance and reasonable API pricing. We also conduct experiments using the cost-efficient smaller version of OpenAI’s

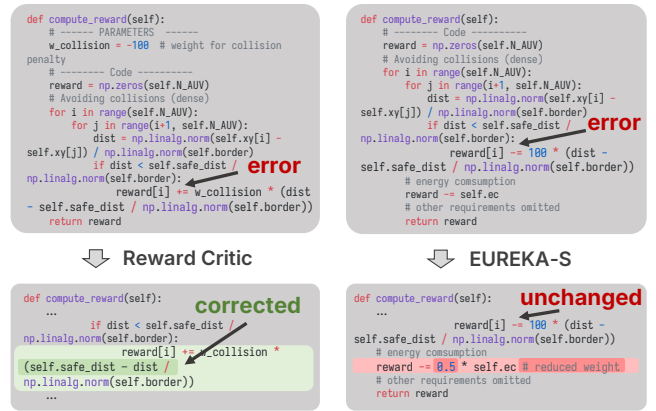


Fig. 2. When the collision penalty term is reversed to a reward term, the reward critic corrects the error, but directly feeding back the entire reward function only results in weight modifications.

LLMs, `gpt-4o-mini-2024-07-18` (denoted as **GPT-4om**). The LLM parameters are set to `temperature=0.5` and `Top P=1`. Similar to Eureka [3], we designed a prompt that takes the reward functions and numerical values as a whole, and this baseline is called as **EUREKA-S**. Meanwhile, we set a baseline called **EUREKA-M**, which processes one or more reward functions along with their training logs summarized by the training log analyzer as inputs during the reward function revision stage, and generates $K=5$ outputs simultaneously. This approach remains consistent with the reward weight searcher, in contrast to generating a single reward function repeatedly in an i.i.d. manner as in Eureka.

B. Main Results and Case Studies

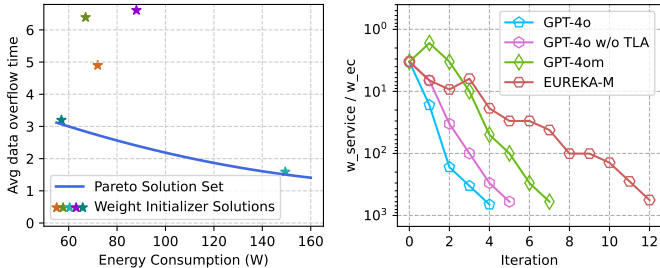
Reward Critic can generate correct code stably and quickly. The initially generated reward functions may not be entirely correct, as they may only contain sparse reward terms, miscalculate distances between AUVs and the boundary, and contain symbolic errors, among other issues. To address these problems, the reward critic generates feedback and revised code for each component. We utilize a variation of the training log analyzer, which outputs [YES] and [NO] to indicate whether a specific component fulfills the requirement. We find that the reward critic can effectively detect various errors and then rewrite reward components based on the description and variables of the environment class. For each component, only one iteration is needed to obtain the correct feedback results.

To investigate the advantages of the reward critic, we manually introduce an elusive error into the reward function by reversing the penalty term for collision into a reward term, namely reversing the symbol `reward -= ...` to `reward += ...`. Example outputs of the reward critic and EUREKA-S are shown in Fig. 2. The reward critic can identify the error, but EUREKA-S fails to do so, only modifying reward weights, even when prompted with "This code contains errors." We also attempted to use the sparse term-only reward function for EUREKA-S to modify, but unless explicitly prompted to generate a dense term, it only continues with weight modification. This suggests that the reward design

TABLE I

THE NUMBER OF ITERATIONS OF SEARCHING WEIGHTS UNDER DIFFERENT EXPERIMENT SETTINGS. THE EXPERIMENT ARE PERFORMED 5 TIMES, AND THE MEAN VALUES AND STANDARD DEVIATIONS ARE REPORTED.

Setting	GPT-4o	GPT-4o w/o TLA	GPT-4om
ERFSL		0.40±0.49	
ERFSL w/o balance	1.20±0.75	1.60±1.02	1.80±1.17
ERFSL 500x off	5.20±1.46	6.40±1.86	8.60±1.74



(a) Solutions generated from the reward weight initializer. (b) Change of maximum value of $w_{\text{service}}/w_{\text{ec}}$ under different settings during iteration.

Fig. 3. Figures of reward weight searching. (a) Solutions generated from the reward weight initializer. (b) Change of step sizes under different settings during iteration.

process based on training feedback may be ineffective without explicit human input.

Reward weight initialization and search. We obtain initial groups of weights from the reward weight initializer, and the energy consumption and average data overflow times (lower is better) of these solutions are illustrated in Fig. 3(a). Although three groups of generated weights do not meet user requirements, two groups (emphasizing timely response to target SNs and energy consumption, respectively) successfully achieve Pareto solutions, indicating that no further search is required, or only a more refined search may be necessary for a specific point on the Pareto set. Then, we employ the reward weight searcher to iteratively adjust the weight coefficients. We also remove the value balance process of the weight initializer (i.e., eliminating the example values from the environment description and removing prompts requiring LLMs to balance reward values, denoted as **ERFSL w/o balance**) to perform comparative experiments. We also perform ablation experiments by removing the training log analyzer (i.e., inputting original training logs directly, denoted as **GPT-4o w/o TLA**). Additionally, we task LLMs to search from a weight group generated by the reward weight initializer, but with the weight of the energy consumption penalty term increased by a factor of 500 (denoted as **500x off**), to understand the search details. Table 1 displays the number of iterations required to meet user demand, while Fig. 3(b) shows the maximum value of $w_{\text{service}}/w_{\text{ec}}$ in five weight groups during training, with the best performance among the five repetitions. When the weight initialization does not consider the balance between reward components, the ratio between weights compared to RWI-initialized settings could differ by a factor of 1 to 50,

leading to a significant increase in the deviation of generated weights. Nevertheless, since the distance is not substantial, only 0-3 iterations are necessary to find a feasible solution.

In the 500x off experiment, **GPT-4o** (GPT-4o with TLA) quickly recognizes excessive energy consumption optimization. It initially uses a 5x search step size, then increases it to expedite the process, and finally reduces it once data overflows decrease, resulting in an average of 5.2 iterations. When the training log analyzer is removed, the choice of step size in complex situations is less flexible compared to **GPT-4o**. We also utilize EUREKA-M as a pure weight searcher for the weight searching process. EUREKA-M adopts small, random step sizes and increases weights in a highly random manner rather than decreasing the penalty of energy consumption, necessitating a substantial number of iterations.

The difference between utilizing GPT-4o and GPT-4om. Intuitively, GPT-4om and open-source LLMs exhibit weaker overall reasoning abilities compared to GPT-4o. Their numerical analysis and mathematical capabilities are also comparatively limited, which leads to poor performance in designing reward functions for robotic control [19]. This limitation results in drawbacks for utilizing GPT-4om in ERFSL, such as an improperly functioning reward function initializer. When responding to content-generating prompts (such as code design and training log analysis) exceeding 5k tokens, the quality of GPT-4om is inferior to that of GPT-4o. Nevertheless, GPT-4om still performs adequately. Similar to GPT-4o, the reward critic requires only one feedback iteration to correct the code per requirement. Furthermore, due to the decomposition of the reward weight searching process, GPT-4o effectively proposes suggestions and completes the process with performance surpassing that of EUREKA-M. However, the step sizes provided by GPT-4om lack flexibility, requiring additional search iterations.

IV. CONCLUSION AND DISCUSSION

In this paper, we propose ERFSL, which decomposes a multi-objective task into clear user requirements, enabling LLMs to function as zero-shot searchers that receive clear feedback and effectively generate reward functions. LLMs are tasked to generate reward components, which are subsequently corrected by the reward critic to prevent potential errors. Leveraging the enhanced numerical calculation capabilities of the latest GPT-4o, we initialize weights that balance the value of reward components, allowing us to obtain feasible Pareto solutions without the need for extensive searching. Furthermore, drawing from non-numerical contexts provided by the training log analyzer, GPT-4o can flexibly adopt different search strategies, including directional mutation and crossover, thereby accelerating the search process. In addition, with the exception of the reward weight initializer, the most prompts exhibit acceptable performance in GPT-4om. Future work may focus on developing clearer and more automated task descriptions and on verifying the LLM-aided reward design process across a broader range of tasks.

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