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Learning To Play the Game of Chess

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Abstract

This paper presents NeuroChess, a program which learns to play chess from the final outcome of games. NeuroChess learns chess board evaluation functions, represented by artificial neural networks. It integrates inductive neural network learning, temporal differencing, and a variant of explanation-based learning. Performance results illustrate some of the strengths and weaknesses of this approach.

1 Introduction

Throughout the last decades, the game of chess has been a major testbed for research on artificial intelligence and computer science. Most of today's chess programs rely on intensive search to generate moves. To evaluate boards, fast evaluation functions are employed which are usually carefully designed by hand, sometimes augmented by automatic parameter tuning methods [1]. Building a chess machine that learns to play solely from the final outcome of games (win/loss/draw) is a challenging open problem in AI.

In this paper, we are interested in learning to play chess from the final outcome of games. One of the earliest approaches, which learned solely by playing itself, is Samuel's famous checker player program [10]. His approach employed *temporal difference learning* (in short: TD) [14], which is a technique for recursively learning an evaluation function. Recently, Tesauro reported the successful application of TD to the game of Backgammon, using artificial neural network representations [16]. While his TD-Gammon approach plays grand-master-level backgammon, recent attempts to reproduce these results in the context of Go [12] and chess have been less successful. For example, Schäfer [11] reports a system just like Tesauro's TD-Gammon, applied to learning to play certain chess endgames. Gherrity [6] presented a similar system which he applied to entire chess games. Both approaches learn purely inductively from the final outcome of games. Tadepalli [15] applied a lazy version of explanation-based learning [5, 7] to endgames in chess. His approach learns from the final outcome, too, but unlike the inductive neural network approaches listed above it learns analytically, by analyzing and generalizing experiences in terms of chess-specific knowledge.

The level of play reported for all these approaches is still below the level of GNU-Chess, a publicly available chess tool which has frequently been used as a benchmark. This illustrates the hardness of the problem of learning to play chess from the final outcome of games.

This paper presents NeuroChess, a program that learns to play chess from the final outcome of games. The central learning mechanisms is the explanation-based neural network (EBNN) algorithm [9, 8]. Like Tesauro's TD-Gammon approach, NeuroChess constructs a neural network evaluation function for chess boards using TD. In addition, a neural network version of explanation-based learning is employed, which analyzes games in terms of a previously learned neural network chess model. This paper describes the NeuroChess approach, discusses several training issues in the domain of chess, and presents results which elucidate some of its strengths and weaknesses.

2 Temporal Difference Learning in the Domain of Chess

Temporal difference learning (TD) [14] comprises a family of approaches to prediction in cases where the event to be predicted may be delayed by an unknown number of time steps. In the context of game playing, TD methods have frequently been applied to learn functions which predict the final outcome of games. Such functions are used as board evaluation functions.

The goal of TD(0), a basic variant of TD which is currently employed in the NeuroChess approach, is to find an evaluation function, V, which ranks chess boards according to their goodness: If the board s is more likely to be a winning board than the board s', then $V(s) > V(s')$. To learn such a function, TD transforms entire chess games, denoted by a sequence of chess boards $s_0, s_1, s_2, \ldots, s_{t_{\text{final}}}$, into training patterns for V. The TD(0) learning rule works in the following way. Assume without loss of generality we are learning white's evaluation function. Then the target values for the *final board* is given by

$$V^{\text{target}}(s_{t_{\text{final}}}) = \begin{cases} 1, & \text{if } s_{t_{\text{final}}} \text{ is a win for white} \\ 0, & \text{if } s_{t_{\text{final}}} \text{ is a draw} \\ -1, & \text{if } s_{t_{\text{final}}} \text{ is a loss for white} \end{cases} \tag{1}$$

and the targets for the intermediate chess boards $s_0, s_1, s_2, \ldots, s_{t_{\text{final}}-2}$ are given by

$$V^{\text{target}}(s_t) = \gamma \cdot V(s_{t+2}) \tag{2}$$

This update rule constructs V recursively. At the end of the game, V evaluates the final outcome of the game (Eq. (1)). In between, when the assignment of V-values is less obvious, V is trained based on the evaluation two half-moves later (Eq. (2)). The constant γ (with $0 \leq \gamma \leq 1$) is a so-called *discount factor*. It decays V exponentially in time and hence favors early over late success. Notice that in NeuroChess V is represented by an artificial neural network, which is trained to fit the target values V^{target} obtained via Eqs. (1) and (2) (*cf.* [6, 11, 12, 16]).

3 Explanation-Based Neural Network Learning

In a domain as complex as chess, pure inductive learning techniques, such as neural network Back-Propagation, suffer from enormous training times. To illustrate why, consider the situation of a *knight fork*, in which the opponent's knight attacks our queen and king simultaneously. Suppose in order to save our king we have to move it, and hence sacrifice our queen. To learn the badness of a knight fork, NeuroChess has to discover that certain board features (like the position of the queen relative to the knight) are important, whereas

Figure 1: **Fitting values and slopes in EBNN:** Let V be the target function for which three examples $\langle s_1, V(s_1)\rangle$, $\langle s_2, V(s_2)\rangle$, and $\langle s_3, V(s_3)\rangle$ are known. Based on these points the learner might generate the hypothesis V'. If the slopes $\frac{\partial V(s_1)}{\partial s_1}$, $\frac{\partial V}{(} s_2)\partial s_2$, and $\frac{\partial V(s_3)}{\partial s_3}$ are also known, the learner can do much better: V''.

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others (like the number of weak pawns) are not. Purely inductive learning algorithms such as Back-propagation figure out the relevance of individual features by observing statistical correlations in the training data. Hence, quite a few versions of a knight fork have to be experienced in order to generalize accurately. In a domain as complex as chess, such an approach might require unreasonably large amounts of training data.

Explanation-based methods (EBL) [5, 7, 15] generalize more accurately from less training data. They rely instead on the availability of domain knowledge, which they use for explaining and generalizing training examples. For example, in the explanation of a knight fork, EBL methods employ knowledge about the game of chess to figure out that the position of the queen is relevant, whereas the number of weak pawns is not. Most current approaches to EBL require that the domain knowledge be represented by a set of symbolic rules. Since NeuroChess relies on neural network representations, it employs a neural network version of EBL, called *explanation-based neural network learning (EBNN)* [9]. In the context of chess, EBNN works in the following way: The domain-specific knowledge is represented by a separate neural network, called the *chess model* M. M maps arbitrary chess boards s_t to the corresponding expected board s_{t+2} two half-moves later. It is trained prior to learning V, using a large database of grand-master chess games. Once trained, M captures important knowledge about temporal dependencies of chess board features in high-quality chess play.

EBNN exploits M to bias the board evaluation function V. It does this by extracting slope constraints for the evaluation function V at all non-final boards, *i.e.*, all boards for which V is updated by Eq. (2). Let

$$\frac{\partial V^{\text{target}}(s_t)}{\partial s_t} \qquad \text{with} \qquad t \in \{0, 1, 2, \ldots, t_{\text{final}} - 2\} \tag{3}$$

denote the target slope of V at s_t, which, because $V^{\text{target}}(s_t)$ is set to $\gamma V(s_{t+2})$ according Eq. (2), can be rewritten as

$$\frac{\partial V^{\text{target}}(s_t)}{\partial s_t} \quad = \quad \gamma \cdot \frac{\partial V(s_{t+2})}{\partial s_{t+2}} \cdot \frac{\partial s_{t+2}}{\partial s_t} \tag{4}$$

using the chain rule of differentiation. The rightmost term in Eq. (4) measures how infinitesimal small changes of the chess board s_t influence the chess board s_{t+2}. It can be approximated by the chess model M:

$$\frac{\partial V^{\text{target}}(s_t)}{\partial s_t} \quad \approx \quad \gamma \cdot \frac{\partial V(s_{t+2})}{\partial s_{t+2}} \cdot \frac{\partial M(s_t)}{\partial s_t} \tag{5}$$

The right expression is only an approximation to the left side, because M is a trained neural

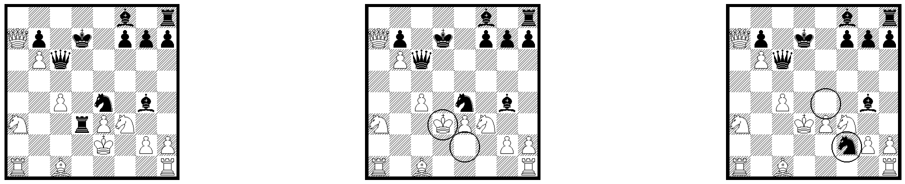

Figure 2: **Learning an evaluation function in NeuroChess.** Boards are mapped into a high-dimensional *feature vector*, which forms the input for both the evaluation network V and the chess model M. The evaluation network is trained by Back-propagation and the TD(0) procedure. Both networks are employed for analyzing training example in order to derive target slopes for V.

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network and thus its first derivative might be erroneous. Notice that both expressions on the right hand side of Eq. (5) are derivatives of neural network functions, which are easy to compute since neural networks are differentiable.

The result of Eq. (5) is an estimate of the slope of the target function V at s_t. This slope adds important shape information to the target values constructed via Eq. (2). As depicted in Fig. 1, functions can be fit more accurately if in addition to target values the slopes of these values are known. Hence, instead of just fitting the target values $V^{\text{target}}(s_t)$, NeuroChess also fits these target slopes. This is done using the Tangent-Prop algorithm [13].

The complete NeuroChess learning architecture is depicted in Fig. 2. The target slopes provide a first-order approximation to the relevance of each chess board feature in the goodness of a board position. They can be interpreted as biasing the network V based on chess-specific domain knowledge, embodied in M. For the relation of EBNN and EBL and the accommodation of inaccurate slopes in EBNN see [8].

4 Training Issues

In this section we will briefly discuss some training issues that are essential for learning good evaluation functions in the domain of chess. This list of points has mainly been produced through practical experience with the NeuroChess and related TD approaches. It illustrates the importance of a careful design of the input representation, the sampling rule and the parameter setting in a domain as complex as chess.

Sampling. The vast majority of chess boards are, loosely speaking, not interesting. If, for example, the opponent leads by more than a queen and a rook, one is most likely to loose. Without an appropriate sampling method there is the danger that the learner spends most of its time learning from uninteresting examples. Therefore, NeuroChess interleaves self-play and expert play for guiding the sampling process. More specifically, after presenting a random number of expert moves generated from a large database of grand-master games, NeuroChess completes the game by playing itself. This sampling mechanism has been found to be of major importance to learn a good evaluation function in a reasonable amount of time.

Quiescence. In the domain of chess certain boards are harder to evaluate than others. For example, in the middle of an ongoing material exchange, evaluation functions often fail to produce a good assessment. Thus, most chess programs search selectively. A common criterion for determining the depth of search is called *quiescence*. This criterion basically detects material threats and deepens the search correspondingly. NeuroChess' search engine does the same. Consequently, the evaluation function V is only trained using quiescent boards.

Smoothness. Obviously, using the raw, canonical board description as input representation is a poor choice. This is because small changes on the board can cause a huge difference in value, contrasting the smooth nature of neural network representations. Therefore, NeuroChess maps chess board descriptions into a set of board features. These features were carefully designed by hand.

Discounting. The variable γ in Eq. (2) discounts values in time. Discounting has frequently been used to bound otherwise infinite sums of pay-off. One might be inclined to think that in the game of chess no discounting is needed, as values are bounded by definition. Indeed, without discounting the evaluation function predicts the *probability* for winning—in the ideal case. In practice, however, random disturbations of the evaluation function can seriously hurt learning, for reasons given in [4, 17]. Empirically we found that learning failed completely when no discount factor was used. Currently, NeuroChess uses $\gamma = 0.98$.

Learning rate. TD approaches minimize a Bellman equation [2]. In the NeuroChess domain, a close-to-optimal approximation of the Bellman equation is the constant function $V(s) \equiv 0$. This function violates the Bellman equation only at the end of games (Eq. (1)), which is rare if complete games are considered. To prevent this, we amplified the learning rate for final values by a factor of 20, which was experimentally found to produce sufficiently non-constant evaluation functions.

Software architecture. Training is performed completely asynchronously on up to 20 workstations simultaneously. One of the workstations acts as a weight server, keeping track of the most recent weights and biases of the evaluation network. The other workstations can dynamically establish links to the weight server and contribute to the process of weight refinement. The main process also monitors the state of all other workstations and restarts processes when necessary. Training examples are stored in local ring buffers (1000 items per workstation).

5 Results

In this section we will present results obtained with the NeuroChess architecture. Prior to learning an evaluation function, the model M (175 input, 165 hidden, and 175 output units) is trained using a database of 120,000 expert games. NeuroChess then learns an evaluation

1. e2e3 b8c6	16. b2b4 a5a4	31. a3f8 f2e4	46. d1c2 b8h2	61. e4f5 h3g4	65. a8e8 e6d7
2. d1f3 c6e5	17. b5c6 a4c6	32. c3b2 h8f8	47. c2c3 f6b6	62. f5f6 h6h5	66. e8e7 d7d8
3. f3d5 d7d6	18. g1f3 d8d6	33. a4d7 f3f5	48. e7e4 g6h6	63. b7b8q g4f5	67. f4c7
4. f1b5 c7c6	19. d4a7 f5g4	34. d7b7 f5e5	49. d4f5 h6g5	64. b8f4 f5e6	
5. b5a4 g8f6	20. c2c4 c8d7	35. b2c1 f8e8	50. e4e7 g5g4		
6. d5d4 c8f5	21. b4b5 c6c7	36. b7d5 e5h2	51. f5h6 g7h6		
7. f2f4 e5d7	22. d2d3 d6d3	37. a1a7 e8e6	52. e7d7 g4h5		
8. e1e2 d8a5	23. b5b6 c7c6	38. d5d8 f6g6	53. d7d1 h5h4		
9. a4b3 d7c5	24. e2d3 e4f2	39. b6b7 e6d6	54. d1d4 h4h3		
10. b1a3 c5b3	25. d3c3 g4f3	40. d8a5 d6c6	55. d4b6 h2e5		
11. a2b3 e7e5	26. g2f3 f2h1	41. a5b4 h2b8	56. b6d4 e5e6		
12. f4e5 f6e4	27. c1b2 c6f3	42. a7a8 e4c3	57. c3d2 e6f5		
13. e5d6 e8c8	28. a7a4 d7e7	43. c2d4 c6f6	58. e3e4 f5g5		
14. b3b4 a5a6	29. a3c2 h1f2	44. b4e7 c3a2	59. d4e3 g5e3		
15. b4b5 a6a5	30. b2a3 e7f6	45. c1d1 a2c3	60. d2e3 f7f5		

final board

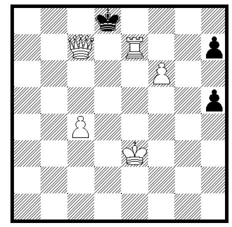

Figure 3: **NeuroChess against GNU-Chess.** NeuroChess plays white. Parameters: Both players searched to depth 3, which could be extended by quiescence search to at most 11. The evaluation network had no hidden units. Approximately 90% of the training boards were sampled from expert play.

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network V (175 input units, 0 to 80 hidden units, and one output units). To evaluate the level of play, NeuroChess plays against GNU-Chess in regular time intervals. Both players employ the same search mechanism which is adopted from GNU-Chess. Thus far, experiments lasted for 2 days to 2 weeks on 1 to 20 SUN Sparc Stations.

A typical game is depicted in Fig. 3. This game has been chosen because it illustrates both the strengths and the shortcomings of the NeuroChess approach. The opening of NeuroChess is rather weak. In the first three moves NeuroChess moves its queen to the center of the board.[1] NeuroChess then escapes an attack on its queen in move 4, gets an early pawn advantage in move 12, attacks black's queen pertinaciously through moves 15 to 23, and successfully exchanges a rook. In move 33, it captures a strategically important pawn, which, after chasing black's king for a while and sacrificing a knight for no apparent reason, finally leads to a new queen (move 63). Four moves later black is mate. This game is prototypical. As can be seen from this and various other games, NeuroChess has learned successfully to protect its material, to trade material, and to protect its king. It has not learned, however, to open a game in a coordinated way, and it also frequently fails to play short endgames even if it has a material advantage (this is due to the short planning horizon). Most importantly, it still plays incredibly poor openings, which are often responsible for a draw or a loss. Poor openings do not surprise, however, as TD propagates values from the end of a game to the beginning.

Table 1 shows a performance comparison of NeuroChess versus GNU-Chess, with and without the explanation-based learning strategy. This table illustrates that NeuroChess wins approximately 13% of all games against GNU-Chess, if both use the same search engine. It

[1] This is because in the current version NeuroChess still heavily uses expert games for sampling. Whenever a grand-master moves its queen to the center of the board, the queen is usually safe, and there is indeed a positive correlation between having the queen in the center and winning in the database. NeuroChess falsely deduces that having the queen in the center is good. This effect disappears when the level of self-play is increased, but this comes at the expense of drastically increased training time, since self-play requires search.

	GNU depth 2, NeuroChess depth 2		GNU depth 4, NeuroChess depth 2	
# of games	Back-propagation	EBNN	Back-propagation	EBNN
100	1	0	0	0
200	6	2	0	0
500	35	13	1	0
1000	73	85	2	1
1500	130	135	3	3
2000	190	215	3	8
2400	239	316	3	11

Table 1: Performance of NeuroChess vs. GNU-Chess during training. The numbers show the total number of games won against GNU-Chess using the same number of games for testing as for training. This table also shows the importance of the explanation-based learning strategy in EBNN. Parameters: both learners used the original GNU-Chess features, the evaluation network had 80 hidden units and search was cut at depth 2, or 4, respectively (no quiescence extensions).

also illustrates the utility of explanation-based learning in chess.

6 Discussion

This paper presents NeuroChess, an approach for learning to play chess from the final outcomes of games. NeuroChess integrates TD, inductive neural network learning and a neural network version of explanation-based learning. The latter component analyzes games using knowledge that was previously learned from expert play. Particular care has been taken in the design of an appropriate feature representation, sampling methods, and parameter settings. Thus far, NeuroChess has successfully managed to beat GNU-Chess in several hundreds of games. However, the level of play still compares poorly to GNU-Chess and human chess players.

Despite the initial success, NeuroChess faces two fundamental problems which both might well be in the way of excellent chess play. Firstly, training time is limited, and it is to be expected that excellent chess skills develop only with excessive training time. This is particularly the case if only the final outcomes are considered. Secondly, with each step of TD-learning NeuroChess loses information. This is partially because the features used for describing chess boards are incomplete, *i.e.*, knowledge about the feature values alone does not suffice to determine the actual board exactly. But, more importantly, neural networks have not the discriminative power to assign arbitrary values to all possible feature combinations. It is therefore unclear that a TD-like approach will ever, for example, develop good chess openings.

Another problem of the present implementation is related to the trade-off between knowledge and search. It has been well recognized that the ultimate cost in chess is determined by the time it takes to generate a move. Chess programs can generally invest their time in search, or in the evaluation of chess boards (search-knowledge trade-off) [3]. Currently, NeuroChess does a poor job, because it spends most of its time computing board evaluations. Computing a large neural network function takes two orders of magnitude longer than evaluating an optimized linear evaluation function (like that of GNU-Chess). VLSI neural network technology offers a promising perspective to overcome this critical shortcoming of sequential neural network simulations.

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