

Learning Crop Management by Reinforcement: gym-DSSAT

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gym-DSSAT

A **gym** environment for realistic crop management tasks, that is easy to use for training Reinforcement Learning (RL) agent with the **Decision Support System for Agrotechnology Transfer (DSSAT)** crop simulator coupled with the **WGEN** stochastic weather generator.

DSSAT: **state-of-the-art** Fortran mechanistic crop growth simulator.

gym: **standardized** Python API to connect a RL agent with a simulator of its environment.

⇒ gym-DSSAT is backed by the PDI library which allows loose coupling interaction between Fortran and Python code.



- gym-DSSAT is an on-going effort: 1st version end of 2021.
- DSSAT offers a vast amount of possible simulations. gym-DSSAT currently handles some of them.
- Beyond DSSAT, our approach may be used to turn other C/C++/Fortran monolithic mechanistic models into RL envs.

Crop management problems in gym-DSSAT

- Fertilization problem:** the agent can apply every day a certain quantity of nitrogen (Table 1). Crops are rainfed, and no irrigation is applied during the growing season. We crafted the default fertilization **return function** as:

$$r(t) = \underbrace{\text{trnu}(t, t+1)}_{\text{plant nitrogen uptake (kg/ha)}} - \underbrace{0.5}_{\text{penalty factor}} \times \underbrace{\text{anfer}(t)}_{\text{fertilizer quantity (kg/ha)}} \quad (1)$$

- Irrigation problem:** the agent can provide every day a certain amount of water to irrigate, as indicated in Table 1.
- Mixed fertilization and irrigation problem:** combines both the aforementioned decision problems, i.e. the agent can fertilize and/or irrigate every day.

Action	Description	Range	DayAfterPlanting	Quantity (kg N/ha)
fertilization	nitrogen amount (kg/ha)	[0,200]	40	27
irrigation	water amount (L/m ²)	[0,50]	45	35
			80	54

Table 1. Daily actions available in gym-DSSAT

Table 2. Expert fertilization policy

Custom scenario definition

- The **observation space** can be easily modified by editing a YAML config. file.
- The **return functions** can also be easily modified by editing a standalone Python file.

Features:

- Soil conditions and weather (simulated or measured) are available off-the-shelf based on **hundreds of example of real-world measures**.
- gym-DSSAT allows built-in climate change (e.g. for atmospheric CO₂, temperature) for **non-stationary** crop management problems.

A use case: learning an efficient maize fertilization

An episode spans one growing season, i.e. a **finite** number of time steps. The objective function is defined as: $\sum_{t=0}^{\text{harvest}} r(t)$.

Table 3 provides the observation space. We consider three policies:

- The **null** policy never fertilizes. As there is always nitrogen in soil before cultivation [3], the reference experiment, or *control*, is the null policy.
- The **expert** policy is the one published in the original maize field experiment [1] and defined in Table 2.
- The **PPO** policy learned by the Proximal Policy Optimization [4] RL algorithm, as implemented in **Stable-Baselines3 1.4.0** [2] with default hyperparameters as baseline. We trained PPO for 10⁶ iterations.

Variable	Definition
istage	DSSAT maize growing stage (categorical)
vstage	vegetative growth stage (number of leaves)
topwt	above the ground crop biomass (kg/ha)
grnwt	grain weight dry matter (kg/ha)
swfac	index of plant water stress (unitless)
nstres	index of plant nitrogen stress (unitless)
xlai	leaf area index (m ² leaf/m ² soil)
dttd	growing degree days (°C.day)
dap	days after planting (day)
cumsumfert	cumulative nitrogen fertilization (kg N/ha)
rain	rainfall for the current day (L/m ² /day)
ep	actual plant transpiration rate (L/m ² /day)

Table 3. Default observation space for the fertilization task

Conclusions from experimental results

- An **untuned** PPO was able to learn sustainable fertilization and irrigation policies.
⇒ RL has a great potential to learn **sustainable crop management practices** using gym-DSSAT.
- gym-DSSAT** allows exploration of many other agricultural decision problems, e.g. multi-year crop management with crop rotations.

If you want to collaborate for developing gym-DSSAT, contact us at:

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References

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Experimental results

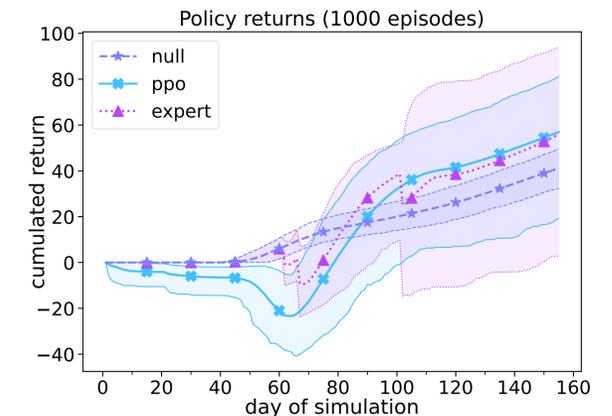


Figure 1. Mean cumulated return of each of the 3 policies against the day of simulation. Shaded area displays the [0.05, 0.95] quantile range for each policy.

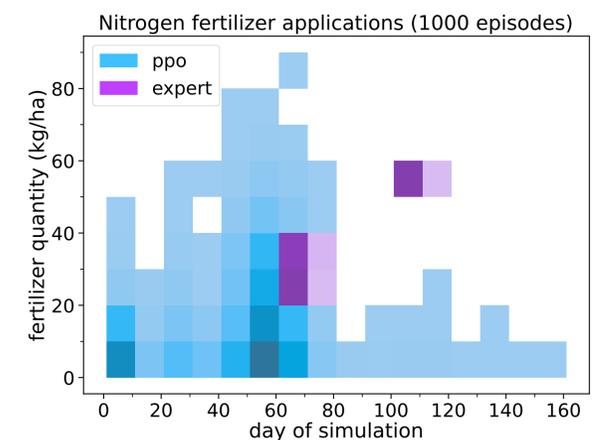


Figure 2. 2D histogram of fertilizer applications (the darker the more frequent).

	null	expert	PPO
grain yield	1141.1 (344.0)	3686.5 (1841.0)	3463.1 (1628.4)
massic nitrogen in grains	1.1 (0.1)	1.7 (0.2)	1.5 (0.3)
total fertilization	0 (0)	115.8 (5.2)	82.8 (15.2)
application number	0 (0)	3.0 (0.1)	5.7 (1.6)
nitrogen use efficiency	n.a.	22.0 (14.1)	28.3 (16.7)
nitrate leaching	15.9 (7.7)	18.0 (12.0)	18.3 (11.6)

Table 4. Mean (st. dev.) of performances computed over 1000 episodes. **Bold** numbers indicate the best performing policy. See Table 5 for interpretation.

Variable	Definition	Comment
grnwt	grain yield (kg/ha)	quantitative objective to be maximized
pcngrn	nitrogen content in grains (%)	qualitative objective to be maximized
cumsumfert	total fertilization (kg/ha)	cost to be minimized
-	application number	cost to be minimized
-	nitrogen use efficiency (kg/kg)	agronomic criteria to be maximized
cleach	nitrate leaching (kg/ha)	loss/pollution to be minimized

Table 5. Performance indicators for fertilization policies. '-' means the variable is not provided by default but it can be derived.