CS 309: Autonomous Intelligent Robotics
FRI I

Lecture 7: AI as Search and PDDL

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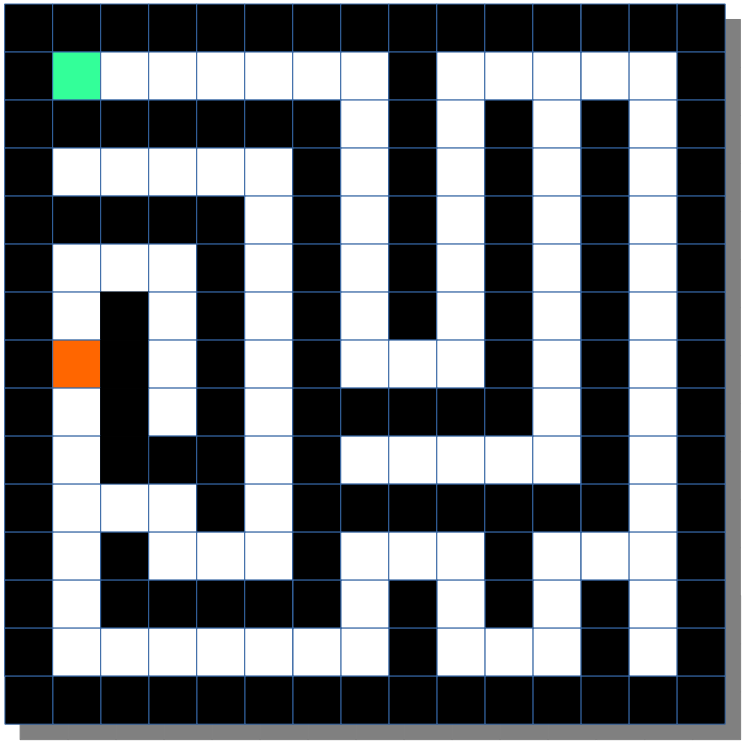
http://justinhart.net/teaching/2018_spring_cs309/

A couple of quick notes

- You should be able to use the lab machines in the 3rd floor computing lab in GDC to do your homework.
- Mentors are available for your help in GDC 3.414
- I have updated the assignment and the header file to be more clear, and to fix some compile errors students reported

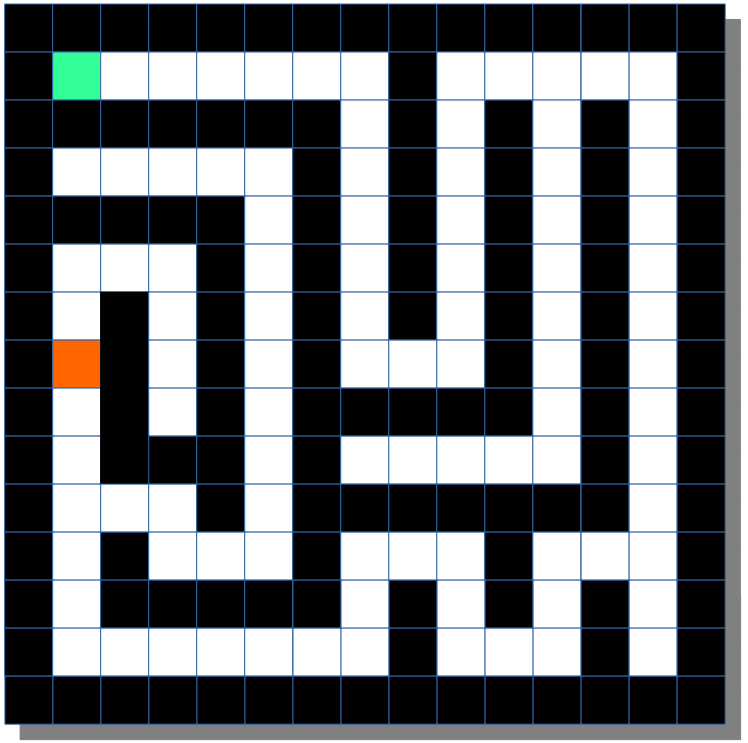
AI as search

- Imagine a computer trying to solve a maze
- There are many options for how to solve this maze
- A search algorithm will test each action an agent can take until it finds a solution



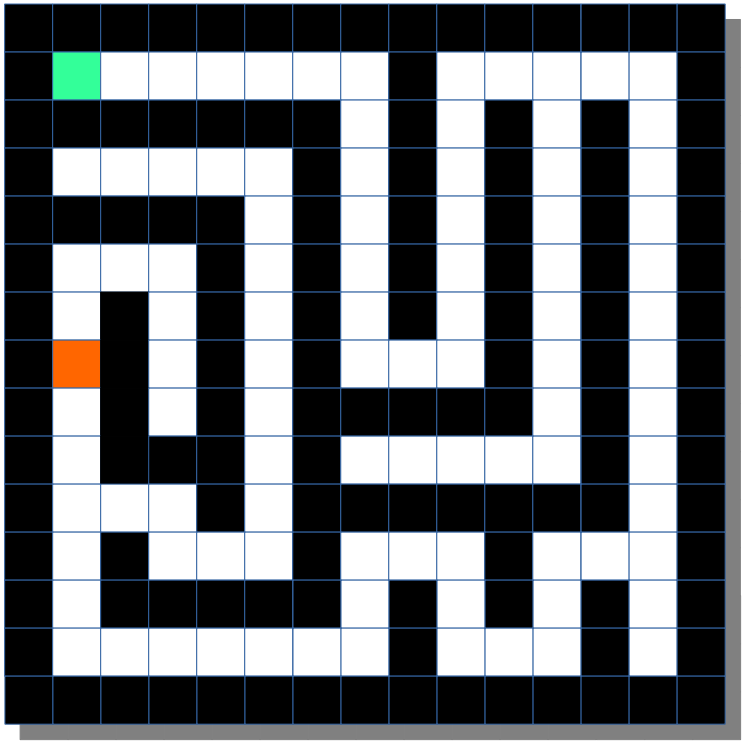
AI as search

- There are two basic types of solutions
  - Satisficing solutions
    - Work, but are not known to be optimal
  - Optimal solutions
    - Are intended to be optimal



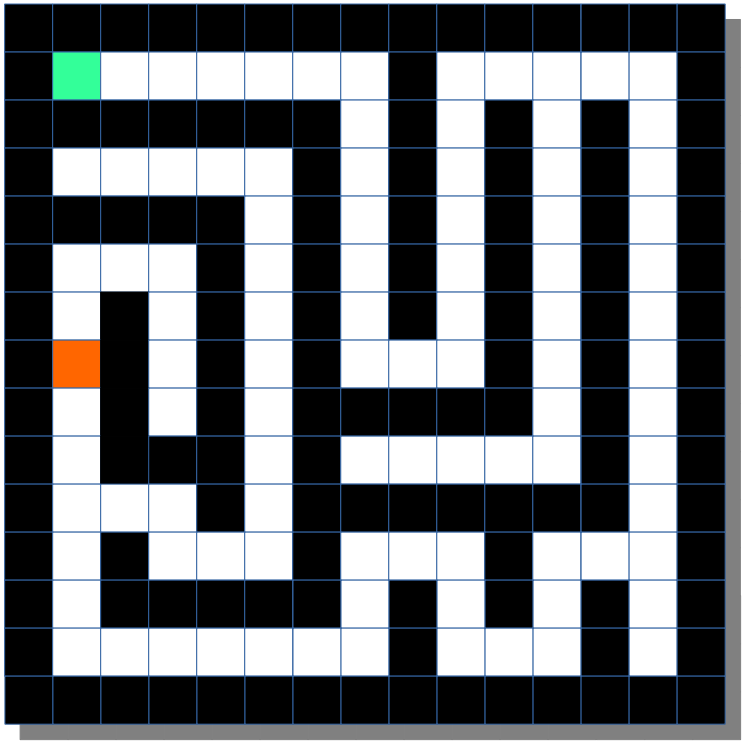
AI as search

- The agent is the orange dot, trying to get to the green dot.
- Possible moves are up, down, left, right.
- Here, left and right are not possible, so when the search algorithm attempts them, they fail.
- Up and down work.



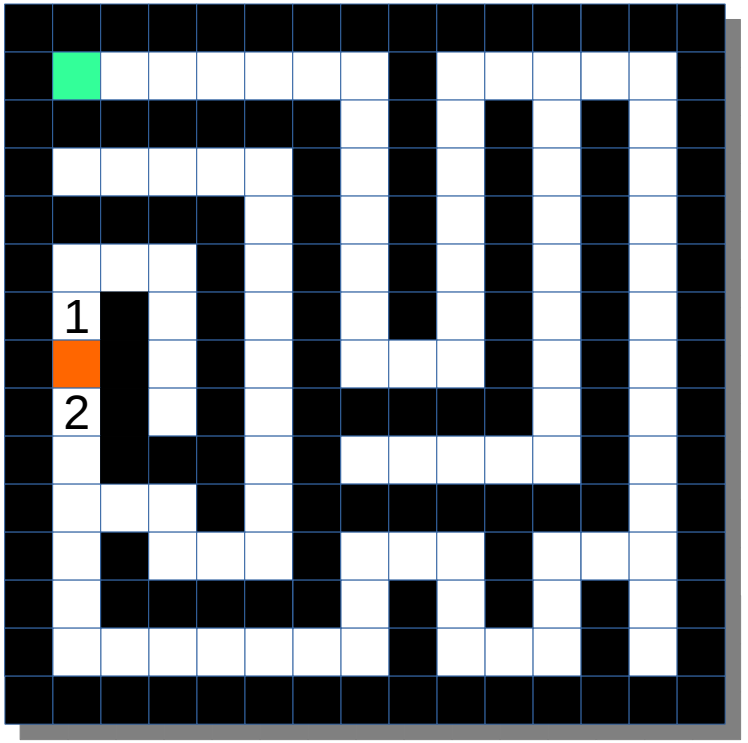
Three basic search patterns

- Breadth-first search
- Depth-first search
- A*



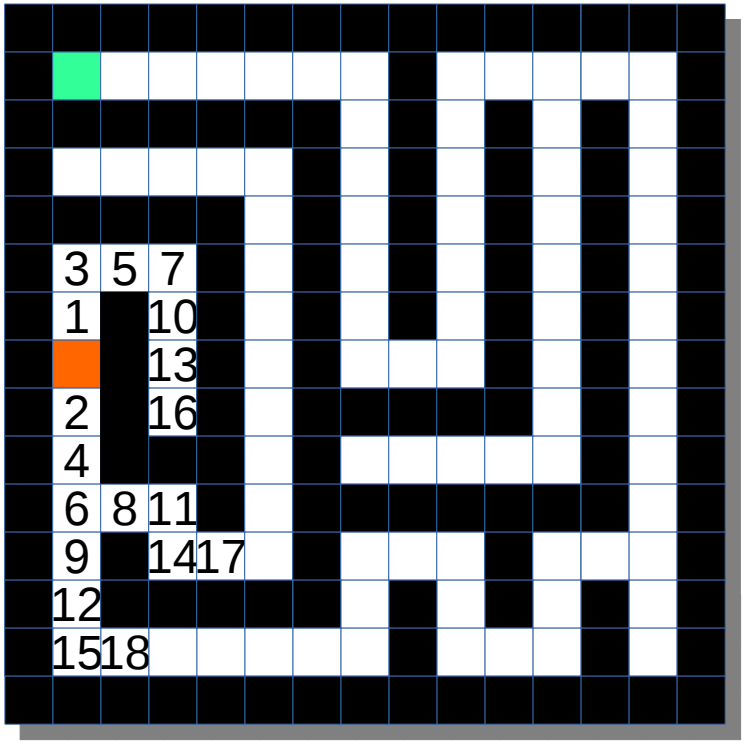
Breadth-first search

- Expand search nodes
  - Up - Works
  - Down - Works
  - Left – Fails
  - Right – Fails
- Enter these into the “ready queue”



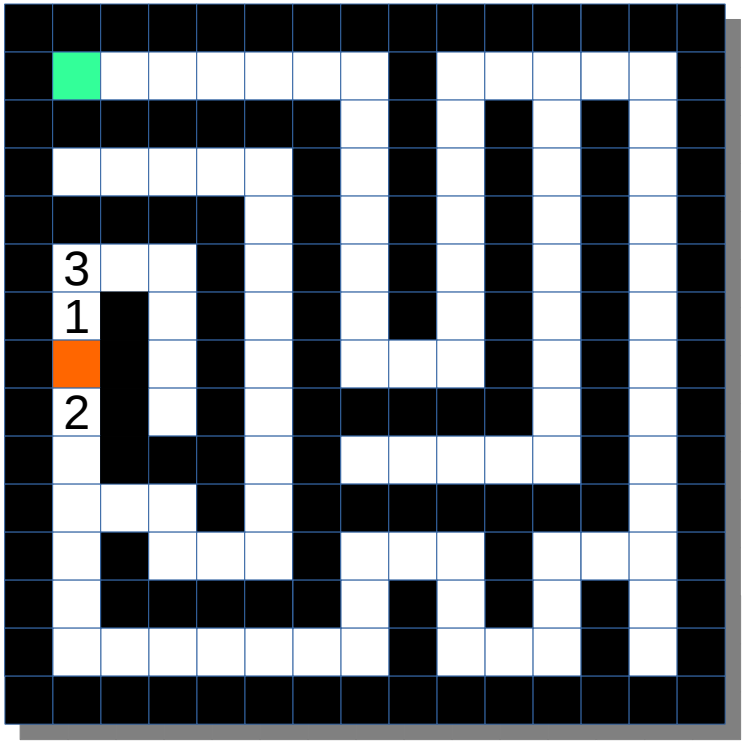
Breadth-first search

- Continue until you have a solution



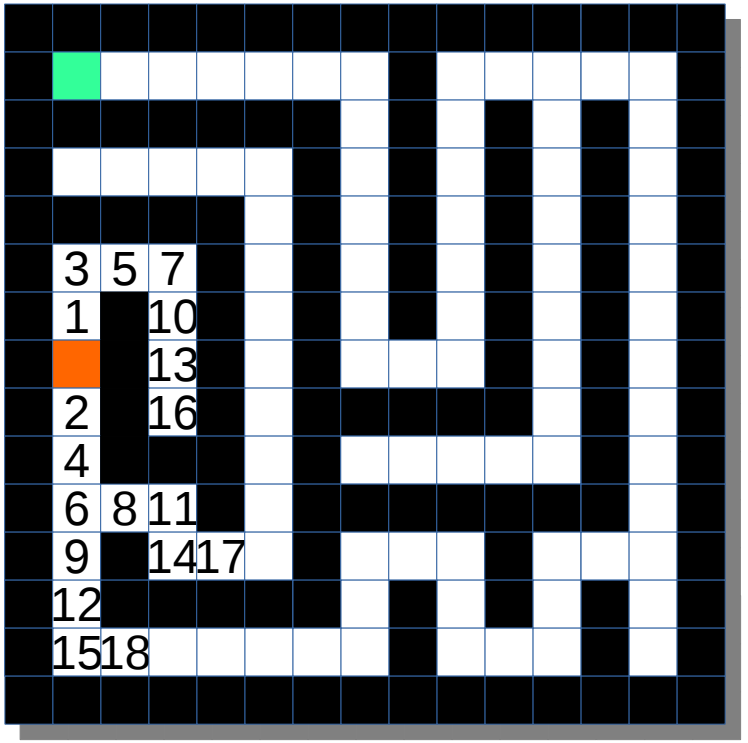
Breadth-first search

- Now try the ones in the ready queue in First In First Out (FIFO) order



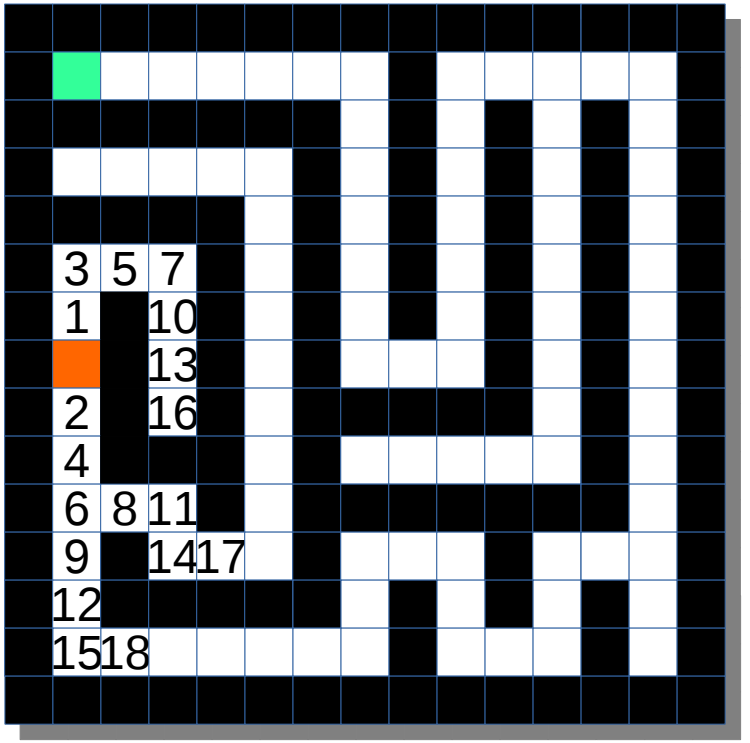
Breadth-first search

- Continue until you have a solution



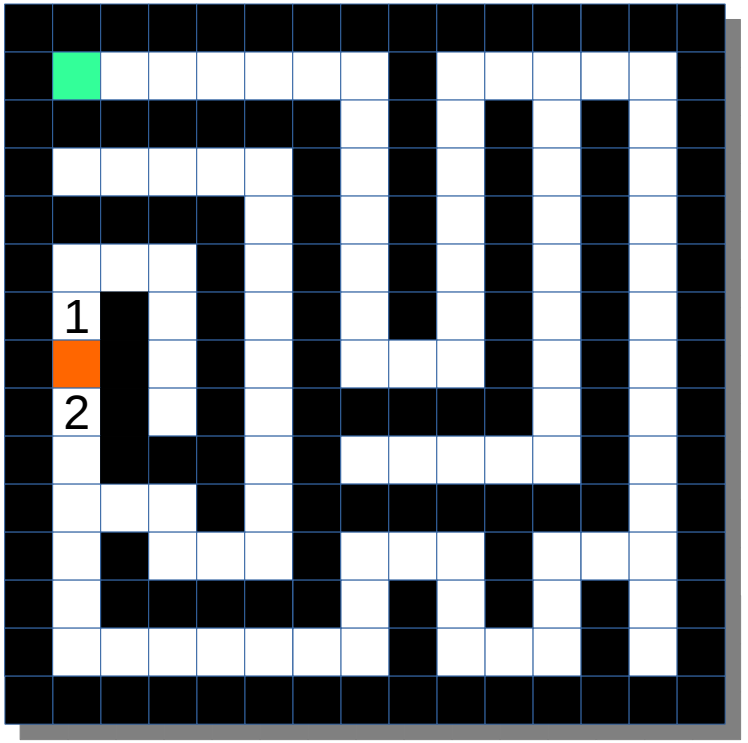
Breadth-first search

- Breadth-first search is “complete” in that in will eventually explore the entire space
- It is “optimal” in that the first solution found takes the fewest steps



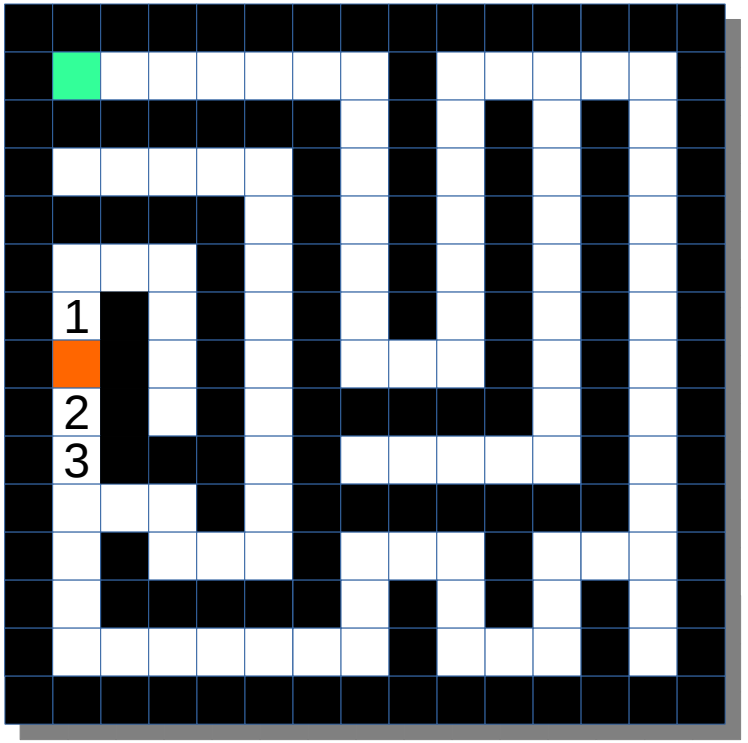
Depth-first search

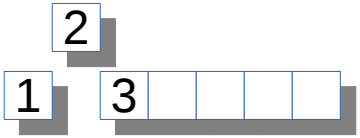
- Depth-first search tries to explore one path completely before moving on
- May faster than breadth-first, but may miss solutions if it takes the first found.



Depth-first search

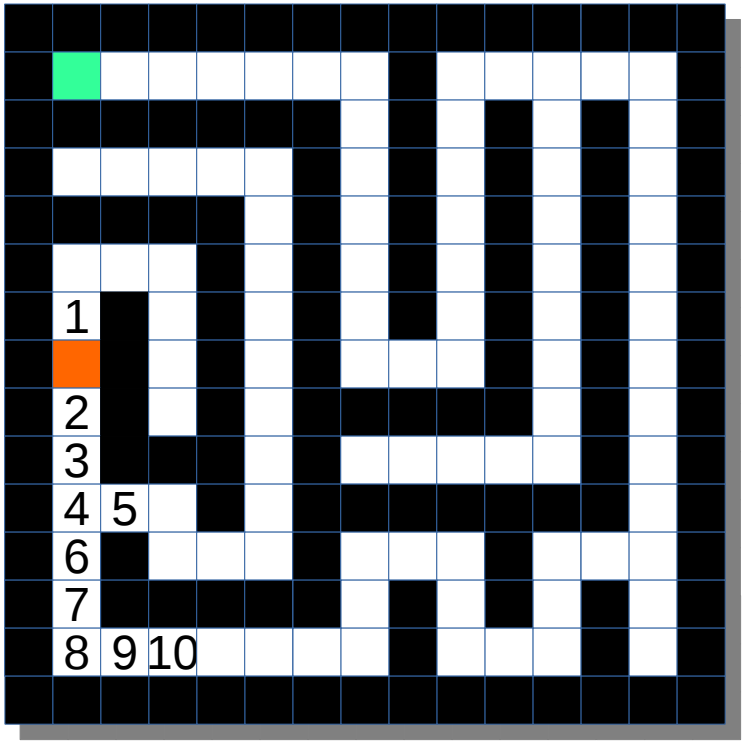
- Uses a First In Last Out (FILO) pattern

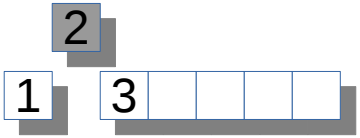




Depth-first search

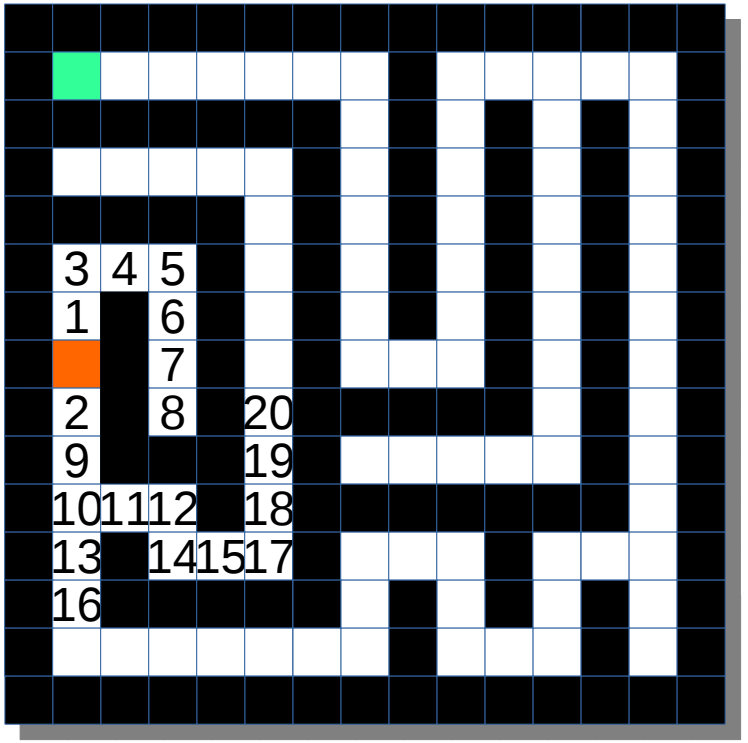
- Uses a First In Last Out (FILO) pattern





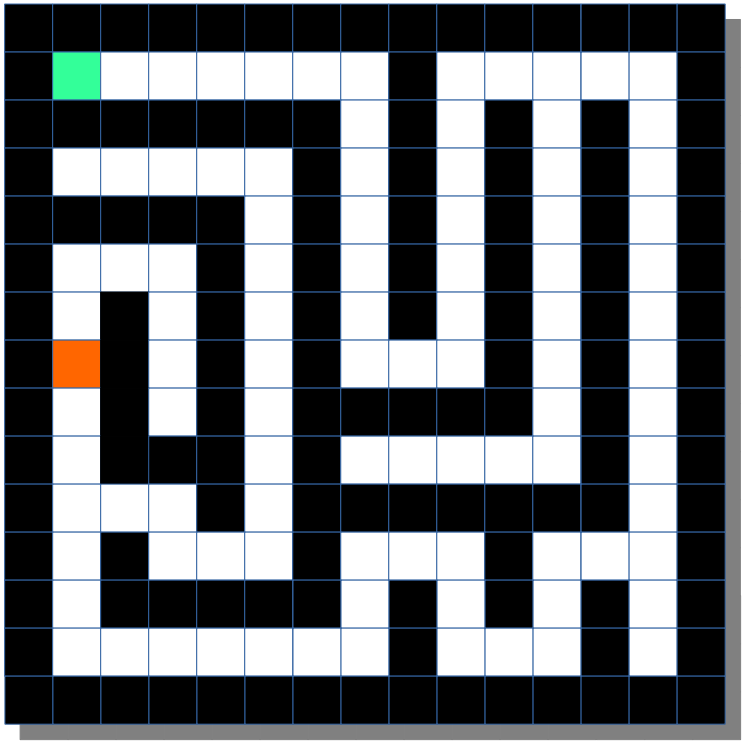
A* search

- The queue becomes a priority queue, with those nodes assumed to have the lowest cost going to the front



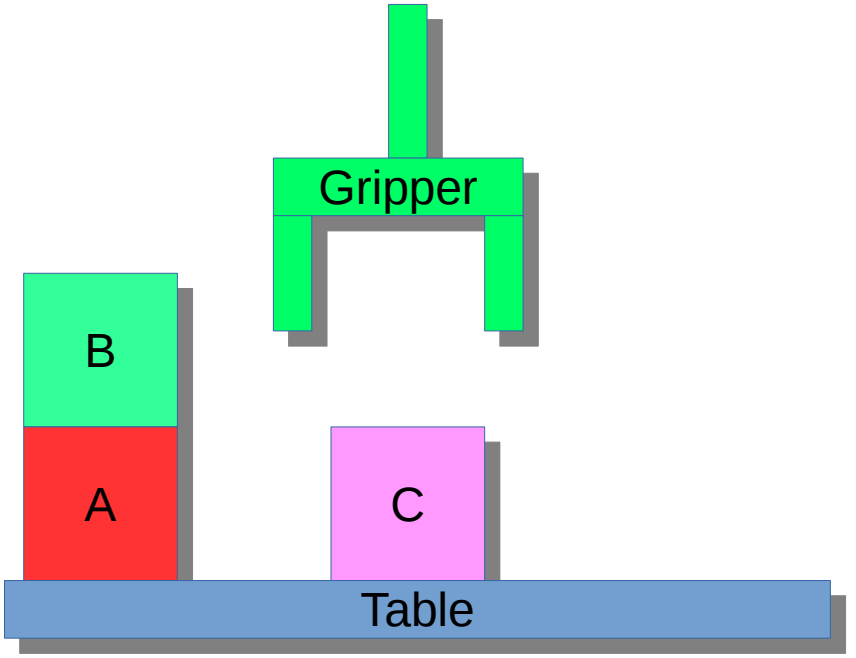
Modern planning

- Planning algorithms have come a long way but still integrate these basic ideas
- The development of these algorithms is often its own class



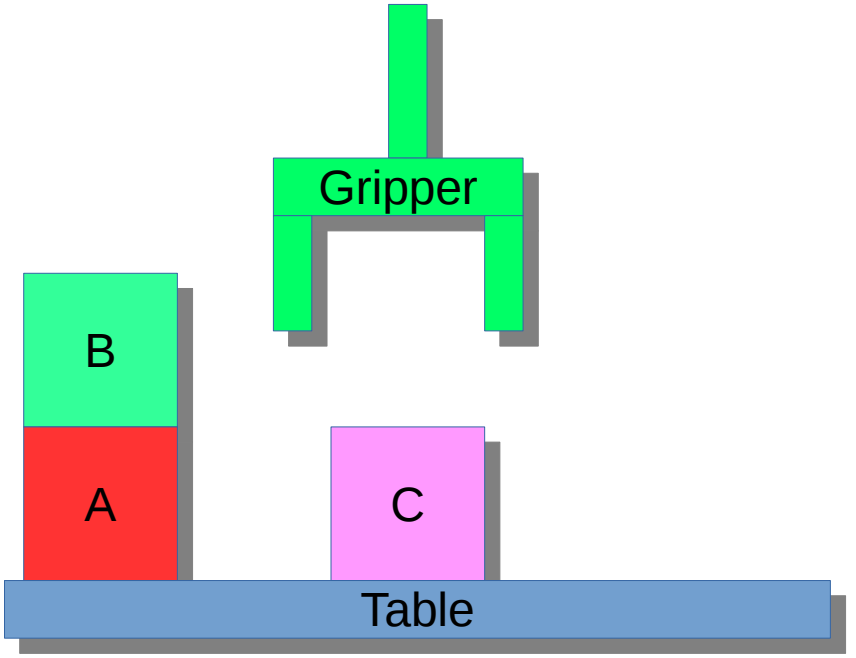
Blocks world

- The planning equivalent of “Hello World” is “Blocks World”
- Blocks arranged on a table with a robot gripper



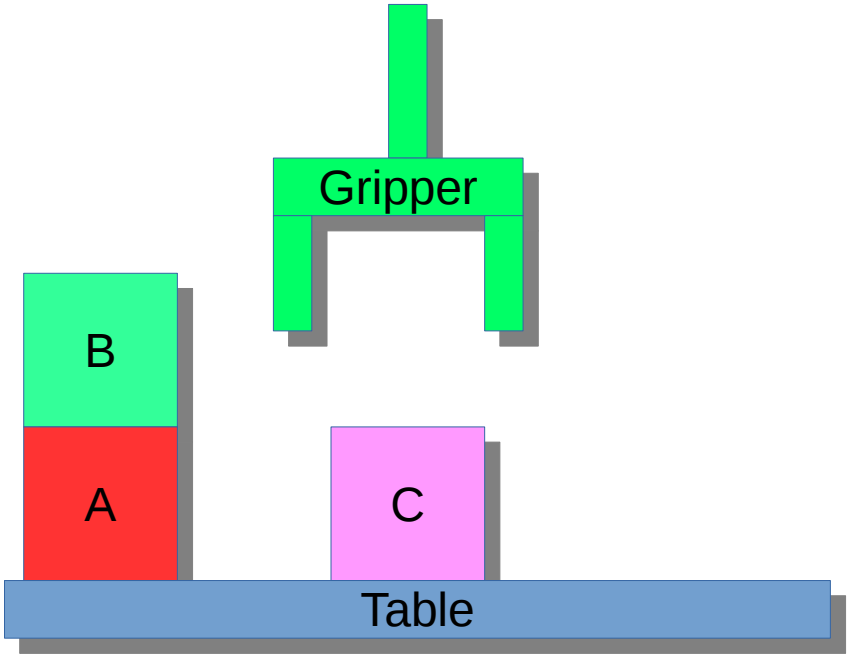
Atoms

- Atoms represent the things we can talk about in the world
  - block_a, block_b, block_c
  - table_a
  - gripper_a



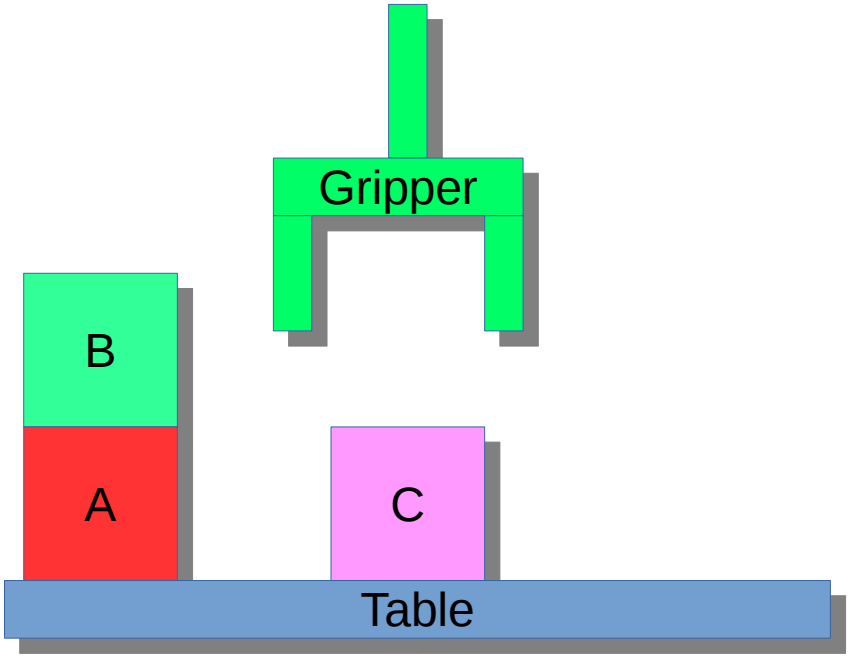
Predicates

- Predicates modify and describe atoms
  - on_table(block_a), on_table(block_c)
  - stacked(block_b, block_a)
  - clear(block_b), clear(block_c)
  - gripper_empty(gripper_a)



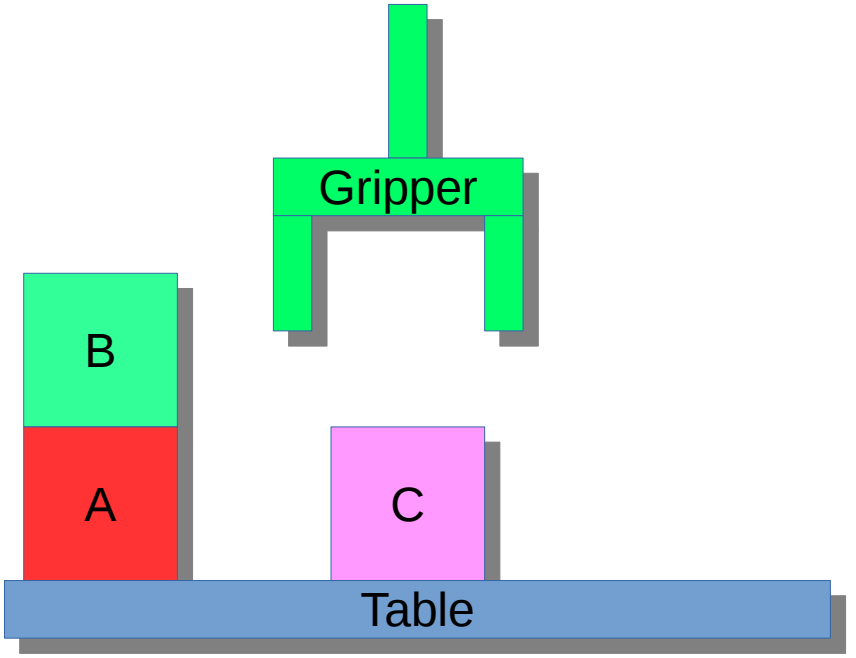
Predicates

- Traditionally, predicates are used like types
  - block(block_a), block(block_b)..
- PDDL has types and type-checking
  - (:types
    block_a, block_b, block_c – block
    gripper_a – gripper
    table_a - table)



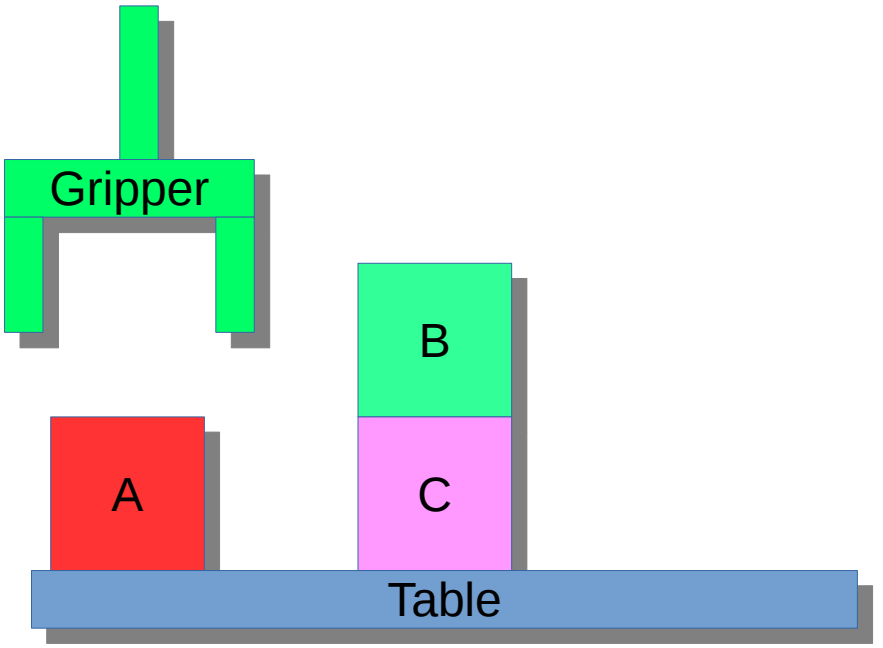
World states

- The predicates used in the previous slide describe the state of the world.
  - on_table(block_a), on_table(block_c)
  - stacked(block_b, block_a)
  - clear(block_b), clear(block_c)
  - gripper_empty(gripper_a)



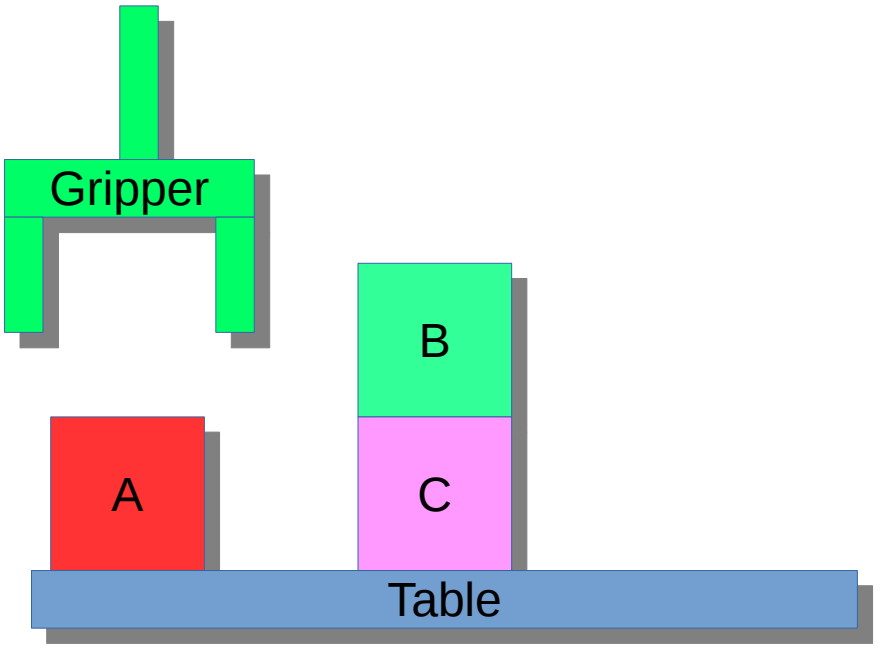
World states

- A different world state would use different predicates
  - on_table(block_a), on_table(block_c)
  - stacked(block_b, block_c)
  - clear(block_b), clear(block_a)
  - gripper_empty(gripper)

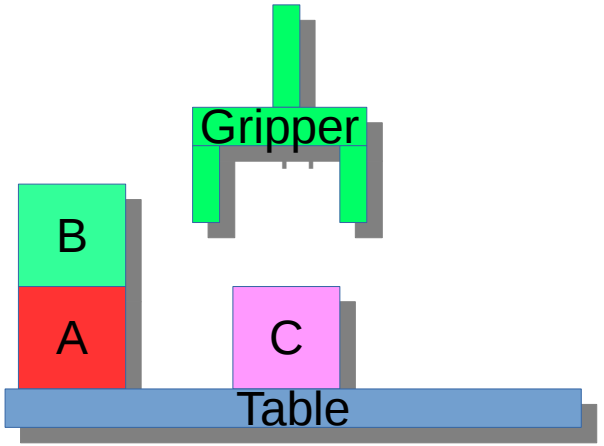


Start states and end states

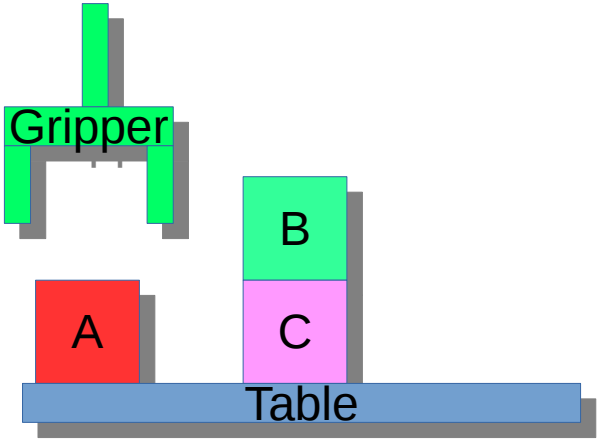
- Start state
  - The current state of the world, or the starting state of your plan
- Goal state
  - The state that you wish to reach



Start states and goal states



- on_table(block_a), on_table(block_c)
- stacked(block_b, block_c)
- clear(block_b), clear(block_a)
- gripper_empty(gripper)

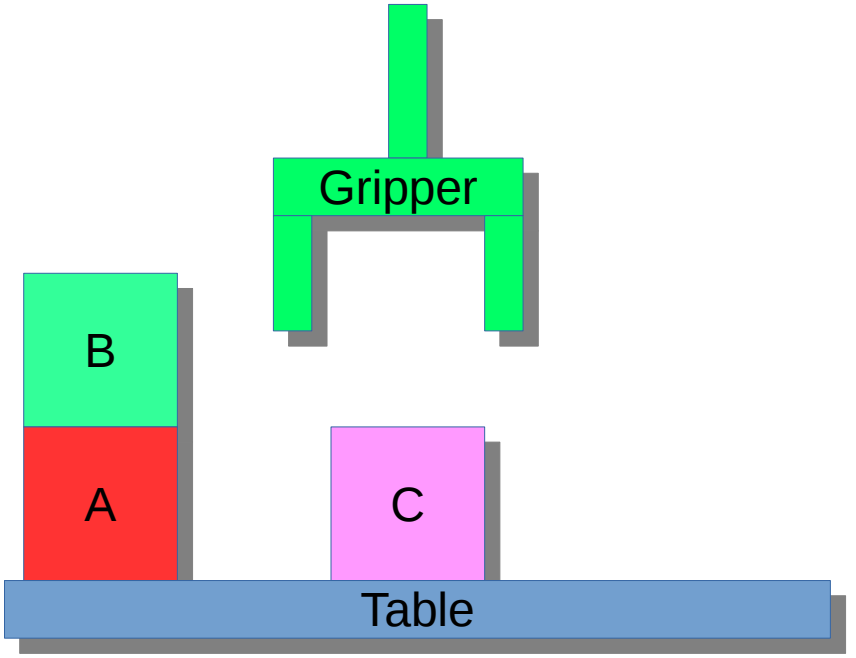


stacked(block_b, block_c)

- While your start state must be complete, generally your goal state can state only those predicates that you require to be true

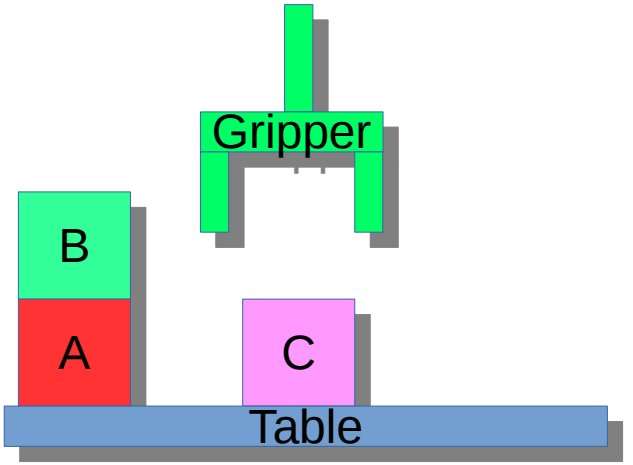
Actions

- Actions permute world state
- Actions have
  - A name
  - Parameters
  - Preconditions
  - Effects



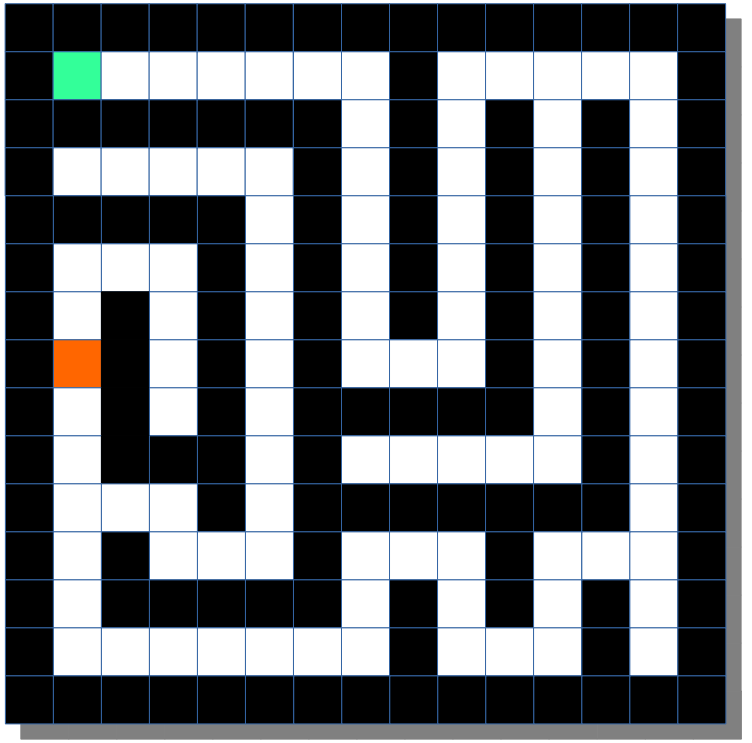
Actions

```
(:action grasp-block
      :parameters (?g – gripper ?b – block)
      :precondition (and (empty ?g) (clear ?b))
      :effect (and
            (not (empty ?g))
            (not (clear ?b))
            (in_gripper ?b ?g)
            )
)
```



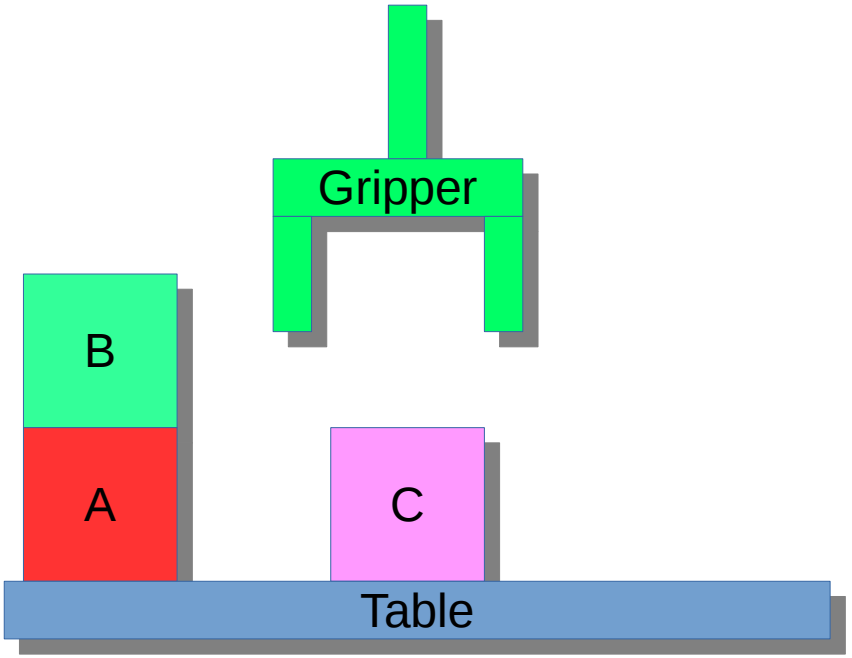
Actions

- Think back to the maze
- Preconditions tell us what must be true for us to be able to take an action
- Effects tell us how the action changes the world
- Our ready queue is filled with possible permutations based on the effects of actions whose preconditions are satisfied
  - Can't go left
  - Can't go right
  - Can go up → resulting in the agent being 1 square up
  - Can go down → resulting in the agent being 1 square down

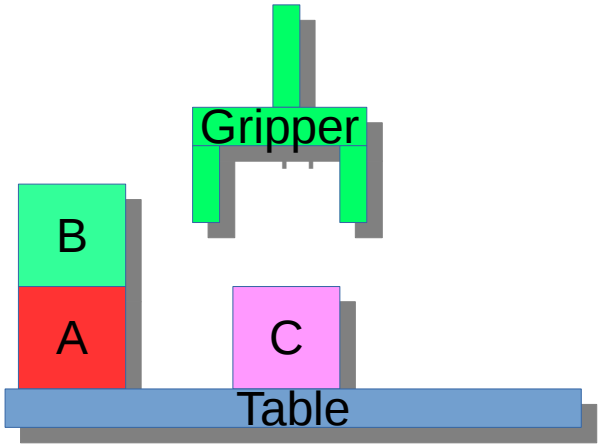


Actions

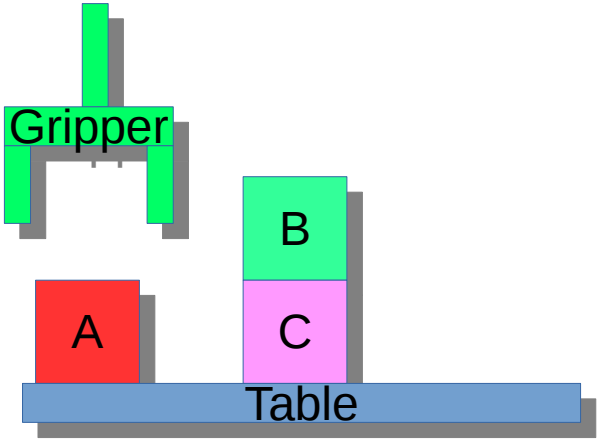
- Can't grasp-block(gripper_a, block_a)
  - So this action isn't taken
- Can grasp-block(gripper_a, block_b)
  - Goes into ready queue
- Can grasp-block(gripper_a, block_c)
  - Goes into ready queue



Plans



A plan takes the world from a start state to a goal state



grasp-block(gripper_a, block_b)

unstack-block(gripper_a, block_b, block_a)

stack-block(gripper_a, block_b, block_c)