CS 1571 Introduction to AI
Lecture 18

Planning: situation calculus

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Automated reasoning systems

Examples and main differences:

- **Theorem provers**
  - Prove sentences in the first-order logic. Use inference rules, resolution rule and resolution refutation.
- **Deductive retrieval systems**
  - Systems based on rules (KBs in Horn form)
  - Prove theorems or infer new assertions (forward, backward chaining)
- **Production systems**
  - Systems based on rules with actions in antecedents
  - Forward chaining mode of operation
- **Semantic networks**
  - Graphical representation of the world, objects are nodes in the graphs, relations are various links

Semantic network systems

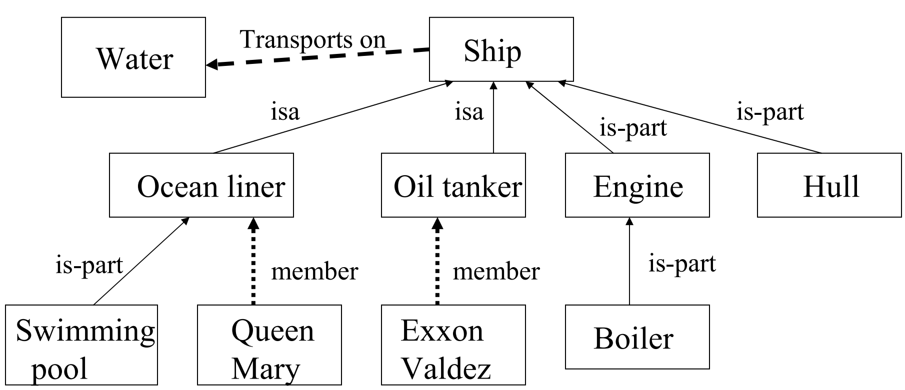
- Knowledge about the world described in terms of graphs. Nodes correspond to:
  - **Concepts or objects** in the domain.

  Links to relations. Three kinds:
  - **Subset links** (isa, part-of links)
  - **Member links** (instance links)
  - **Function links**.

  Inheritance relation links

- Can be transformed to the first-order logic language
- Graphical representation is often easier to work with
  - better overall view on individual concepts and relations

Semantic network. Example.



Inferred properties: *Queen Mary is a ship*
Queen Mary has a boiler

Planning: situation calculus

Representation of actions, situations, events

The world is dynamic:
- What is true now may not be true tomorrow
- Changes in the world may be triggered by our activities

Problems:
- Logic (FOL) as we had it referred to a static world. How to represent the change in the FOL ?
- How to represent actions we can use to change the world?

Planning problem:
- find a sequence of actions that achieves some goal in this complex world?
- A very complex **search problem**

Situation calculus

Provides a framework for representing change, actions and for reasoning about them

- **Situation calculus**
  - based on the first-order logic,
  - a situation variable models new states of the world
  - action objects model activities
  - uses inference methods developed for FOL to do the reasoning

Situation calculus

- Logic for reasoning about changes in the state of the world
- **The world is described by:**
  - Sequences of **situations** of the current state
  - Changes from one situation to another are **caused by actions**
- **The situation calculus allows us to:**
  - Describe the **initial state and a goal state**
  - Build the **KB that describes the effect of actions** (operators)
  - Prove that the KB and the initial state lead to a goal state
    - extracts a plan as side-effect of the proof

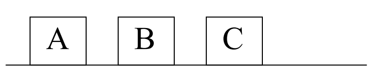
Situation calculus

The language is based on the First-order logic plus:

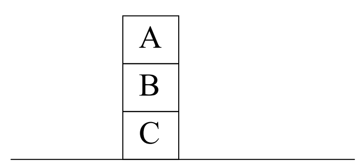
- **Special variables:** s,a – objects of type situation and action
- **Action functions:** return actions.
  - E.g. *Move(A, TABLE, B)* represents a move action
  - *Move(x,y,z)* represents an action schema
- **Two special function symbols of type situation**
  - s_0 – initial situation
  - *DO(a,s)* – denotes the situation obtained after performing an action a in situation s
- **Situation-dependent functions and relations**

  (also called **fluents**)
  - **Relation:** *On(x,y,s)* – object x is on object y in situation s;
  - **Function:** Above(x,s) – object that is above x in situation s.

Situation calculus. Blocks world example.



Initial state



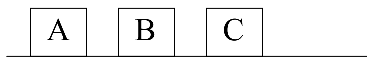
Goal

On(A,Table, s_0)
On(B,Table, s_0)
On(C,Table, s_0)
Clear(A, s_0)
Clear(B, s_0)
Clear(C, s_0)
Clear(Table, s_0)

Find a state (situation) s, such that

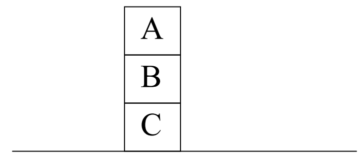
On(A,B, s)
On(B,C, s)
On(C,Table, s)

Blocks world example.



Initial state

$On(A, Table, s_0)$
$On(B, Table, s_0)$
$On(C, Table, s_0)$
$Clear(A, s_0)$
$Clear(B, s_0)$
$Clear(C, s_0)$
$Clear(Table, s_0)$



Goal

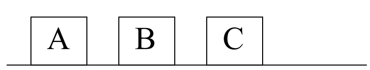
$On(A,B, s)$
$On(B,C, s)$
$On(C, Table, s)$

Note: It is not necessary that the goal describes all relations

$Clear(A, s)$

Blocks world example.

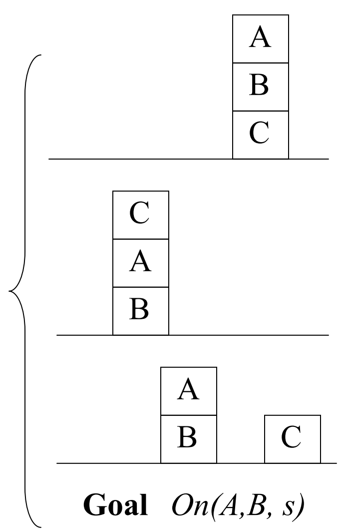
Assume a simpler goal $On(A,B, s)$



Initial state

$On(A, Table, s_0)$
$On(B, Table, s_0)$
$On(C, Table, s_0)$
$Clear(A, s_0)$
$Clear(B, s_0)$
$Clear(C, s_0)$
$Clear(Table, s_0)$

3 possible goal configurations



Goal $On(A,B, s)$

Knowledge base: Axioms.

Knowledge base needed to support the reasoning:

- Must represent changes in the world due to actions.

Two types of axioms:

- **Effect axioms**
  - changes in situations that result from actions
- **Frame axioms**
  - things preserved from the previous situation

Blocks world example. Effect axioms.

Effect axioms:

Moving x from y to z. $MOVE(x, y, z)$

Effect of move changes on **On** relations

$$On(x, y, s) \wedge Clear(x, s) \wedge Clear(z, s) \rightarrow On(x, z, DO(MOVE(x, y, z), s))$$

$$On(x, y, s) \wedge Clear(x, s) \wedge Clear(z, s) \rightarrow \neg On(x, y, DO(MOVE(x, y, z), s))$$

Effect of move changes on **Clear** relations

$$On(x, y, s) \wedge Clear(x, s) \wedge Clear(z, s) \rightarrow Clear(y, DO(MOVE(x, y, z), s))$$

$$On(x, y, s) \wedge Clear(x, s) \wedge Clear(z, s) \wedge (z \neq Table) \rightarrow \neg Clear(z, DO(MOVE(x, y, z), s))$$

Blocks world example. Frame axioms.

- **Frame axioms.**
  - Represent things that remain unchanged after an action.

On relations:

$$On(u,v,s) \wedge (u \neq x) \wedge (v \neq y) \rightarrow On(u,v,DO(MOVE(x,y,z),s))$$

Clear relations:

$$Clear(u,s) \wedge (u \neq z) \rightarrow Clear(u,DO(MOVE(x,y,z),s))$$

Planning in situation calculus

Planning problem:

- find a sequence of actions that lead to a goal

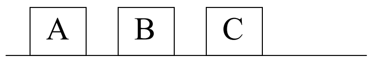
Planning in situation calculus is converted to the theorem proving problem

Goal state:

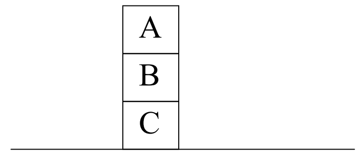
$$\exists s\ On(A,B,s) \wedge On(B,C,s) \wedge On(C,Table,s)$$

- Possible inference approaches:
  - **Inference rule approach**
  - **Conversion to SAT**
- **Plan** (solution) is a byproduct of theorem proving.
- **Example:** blocks world

Planning in a blocks world.



Initial state

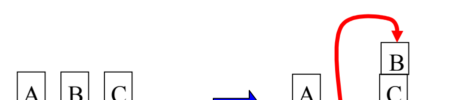


Goal

On(A,Table, s_0)
On(B,Table, s_0)
On(C,Table, s_0)
Clear(A, s_0)
Clear(B, s_0)
Clear(C, s_0)
Clear(Table, s_0)

On(A,B, s)
On(B,C, s)
On(C,Table, s)

Planning in the blocks world.



Initial state (s0) **s1**

$s_0 =$

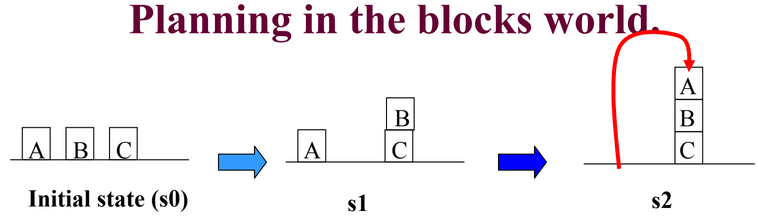
$On(A, Table, s_0)$ $Clear(A, s_0)$ $Clear(Table, s_0)$
$On(B, Table, s_0)$ $Clear(B, s_0)$
$On(C, Table, s_0)$ $Clear(C, s_0)$

Action: $MOVE(B, Table, C)$

$s_1 = DO(MOVE(B, Table, C), s_0)$

$On(A, Table, s_1)$ $Clear(A, s_1)$ $Clear(Table, s_1)$
$On(B, C, s_1)$ $Clear(B, s_1)$
$\neg On(B, Table, s_1)$ $\neg Clear(C, s_1)$
$On(C, Table, s_1)$

Planning in the blocks world.



$s_1 = DO(MOVE(B, Table, C), s_0)$

$On(A, Table, s_1)$ $\quad Clear(A, s_1)$ $\quad Clear(Table, s_1)$

$On(B, C, s_1)$ $\quad Clear(B, s_1)$

$\neg On(B, Table, s_1)$ $\quad \neg Clear(C, s_1)$

$On(C, Table, s_1)$

Action: $MOVE(A, Table, B)$

$s_2 = DO(MOVE(A, Table, B), s_1)$

$= DO(MOVE(A, Table, B), DO(MOVE(B, Table, C), s_0))$

$On(A, B, s_2)$ $\quad \neg On(A, Table, s_2)$ $\quad \neg Clear(B, s_2)$

$On(B, C, s_2)$ $\quad \neg On(B, Table, s_2)$ $\quad \neg Clear(C, s_2)$

$On(C, Table, s_2)$ $\quad Clear(A, s_2)$ $\quad Clear(Table, s_2)$

Planning in situation calculus.

Planning problem:

- Find a sequence of actions that lead to a goal
- Is a special type of a search problem
- Planning in situation calculus is converted to theorem proving.

- **Problems:**
  - Large search space
  - Large number of axioms to be defined for one action
  - Proof may not lead to the best (shortest) plan.