CS 1571 Introduction to AI
Lecture 18

Planning: STRIPS and POP planners

Milos Hauskrecht
milos@cs.pitt.edu
5329 Sennott Square

Representation of actions, situations, events

Propositional and first order logic assume a static world
- Once something is true it cannot become false

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

Problems:
- How to represent the change in the FOL ?
- How to represent actions we can use to change the world?

Planning

Planning problem:

- find a sequence of actions that achieves some goal
- an instance of a search problem
- the state description is typically very complex and relies on a logic-based representation

Methods for modeling and solving a planning problem:

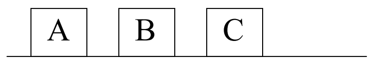
- State space search
- Situation calculus based on FOL
- STRIPS – state space search algorithm
- Partial-order planning algorithms

Situation calculus

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

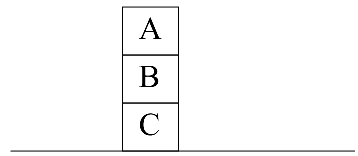
- **Situation calculus**
  - based on the first-order logic
- **How does it represent time?**
- Uses a situation variable that models new states of the world
- Example: On(x,y,s)
- **How does it represent the change due to actions?**
- effect and frame axioms
- **What inference method it uses?**
- Inference rules, Resolution refutation

Situation calculus. 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

Find a state (situation) s, such that

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

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

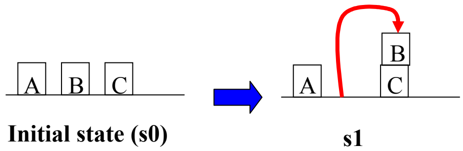
Planning in situation calculus is converted to the theorem proving problem

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 the blocks world.



$s_0 =$

$On(A, Table, s_0)$ $\quad$ $Clear(A, s_0)$ $\quad$ $Clear(Table, s_0)$

$On(B, Table, s_0)$ $\quad$ $Clear(B, s_0)$

$On(C, Table, s_0)$ $\quad$ $Clear(C, s_0)$

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

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

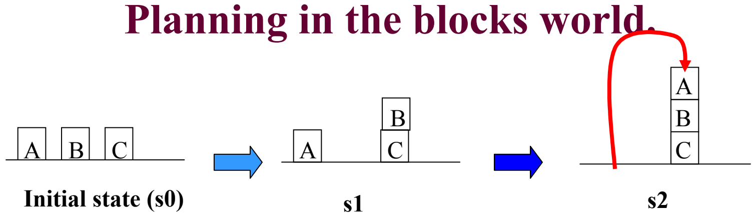
$On(A, Table, s_1)$ $\quad$ $Clear(A, s_1)$ $\quad$ $Clear(Table, s_1)$

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

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

$On(C, Table, s_1)$

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
  - All 'unchanged' properties/relations must be explicitly moved to the next situation
  - Proof may not lead to the best (shortest) plan.

Problems and Solutions

- **Complex state description and local action effects:**
  - avoid the enumeration and inference of every state component, focus on changes only

- **Many possible actions:**
  - Apply actions that make progress towards the goal
  - Understand what the effect of actions is and reason with the consequences

- **Sequences of actions in the plan can be too long:**
  - Many goals consists of independent or nearly independent sub-goals
  - Allow goal decomposition & divide and conquer strategies

STRIPS planner

Defines a **restricted representation language** as compared to the situation calculus

Advantage: leads to more efficient planning algorithms.

– State-space search with structured representations of states, actions and goals
– Action representation avoids the frame problem

STRIPS planning problem:

- much like a standard search problem

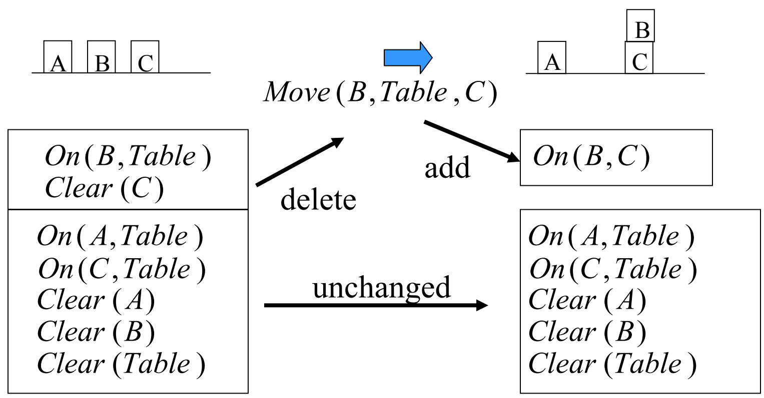
STRIPS planner

- **States:**
  – conjunction of literals, e.g. *On(A,B), On(B,Table), Clear(A)*
  – represent facts that are true at a specific point in time
- **Actions (operators):**
  – **Action:** *Move (x,y,z)*
  – **Preconditions:** conjunctions of literals with variables
  On(x,y), Clear(x), Clear(z)
  – **Effects.** Two lists:
    - **Add list:** *On(x,z), Clear(y)*
    - **Delete list:** *On(x,y), Clear(z)*
    - Everything else remains untouched (is preserved)

STRIPS planning

Operator: *Move (x,y,z)*

- **Preconditions:** *On(x,y), Clear(x), Clear(z)*
- **Add list:** *On(x,z), Clear(y)*
- **Delete list:** *On(x,y), Clear(z)*



STRIPS planning

Initial state:

- Conjunction of literals that are true

Goals in STRIPS:

- A goal is a partially specified state
- Is defined by a conjunction of ground literals
  - No variables allowed in the description of the goal

Example:

$On(A,B) \wedge On(B,C)$

Search in STRIPS

Objective:

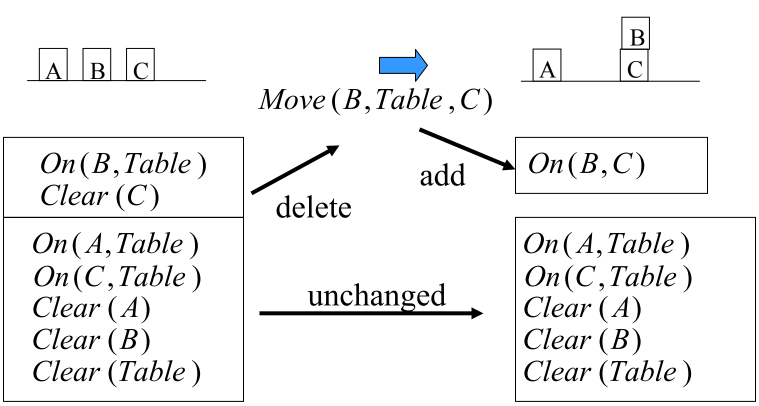
Find a sequence of operators (a plan) from the initial state to the state satisfying the goal

Two approaches to build a plan:

- **Forward state space search (goal progression)**
  - Start from what is known in the initial state and apply operators in the order they are applied
- **Backward state space search (goal regression)**
  - Start from the description of the goal and identify actions that help to reach the goal

Forward search (goal progression)

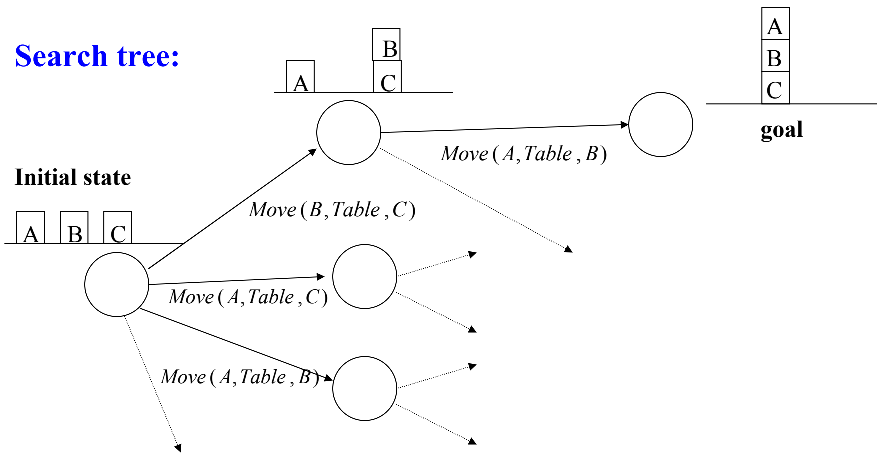
- **Idea:** Given a state *s*
  - Unify the preconditions of some operator *a* with *s*
  - Add and delete sentences from the add and delete list of an operator *a* from *s* to get a new state



Forward search (goal progression)

- Use operators to generate new states to search
- Check new states whether they satisfy the goal

Search tree:



Forward search (goal progression)

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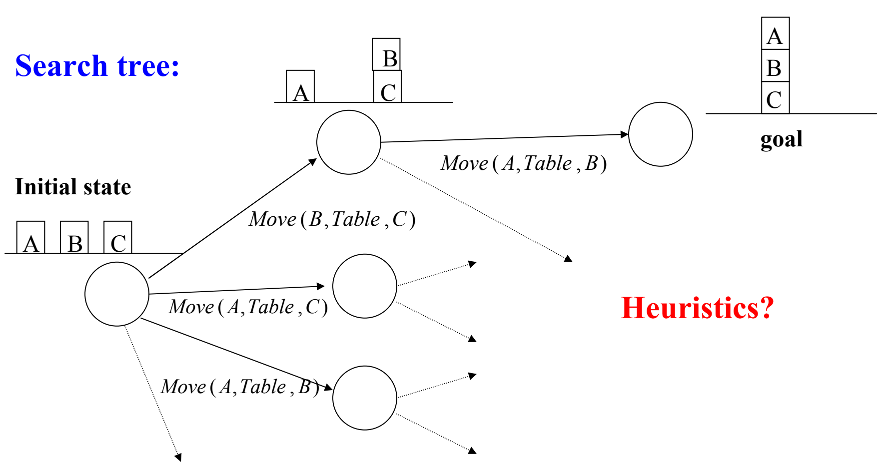
Search tree:

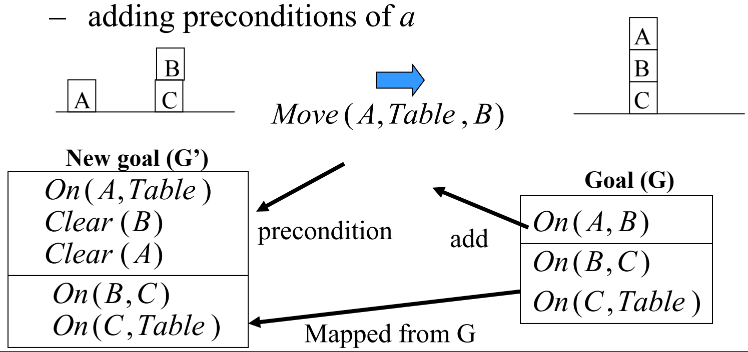


Heuristics?

Backward search (goal regression)

Idea: Given a goal *G*

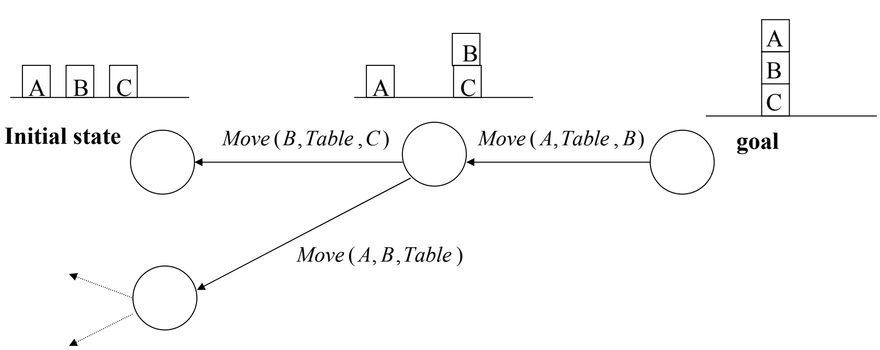
- Unify the add list of some operator *a* with a subset of *G*
- If the delete list of *a* does not remove elements of *G*, then the goal regresses to a new goal *G'* that is obtained from *G* by:
  – deleting add list of *a*
  – adding preconditions of *a*



Backward search (goal regression)

- Use operators to generate new goals
- Check whether the initial state satisfies the goal

Search tree:



State-space search

- **Forward and backward state-space planning approaches:**
  - Work with strictly linear sequences of actions

- **Disadvantages:**
  - They cannot take advantage of the **problem decompositions** in which the goal we want to reach consists of a set of independent or nearly independent sub-goals
  - Action sequences cannot be **built from the middle**
  - No mechanism to represent **least commitment** in terms of the action ordering

Divide and conquer

- **Divide and conquer strategy**:
  - divide the problem to a set of smaller sub-problems,
  - solve each sub-problem independently
  - combine the results to form the solution

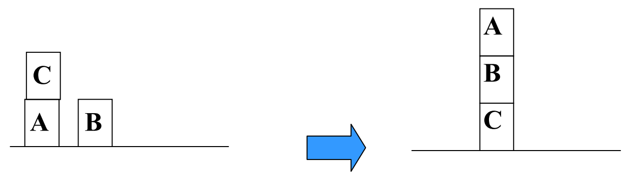
In planning we would like to satisfy a set of goals

- **Divide and conquer in planning:**
  - Divide the planning goals along individual goals
  - Solve (find a plan for) each of them independently
  - Combine the plan solutions in the resulting plan

- Is it always safe to use divide and conquer?
  - No. There can be interacting goals.

Sussman's anomaly.

- An example from the blocks world in which the divide and conquer fails due to interacting goals

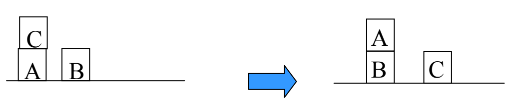


Initial state **Goal**

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

Sussman's anomaly

1. Assume we want to satisfy $On(A, B)$ first

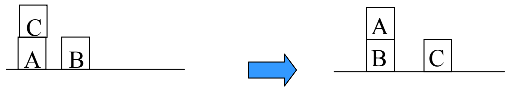


Initial state

But now we cannot satisfy $On(B, C)$ without undoing $On(A, B)$

Sussman's anomaly

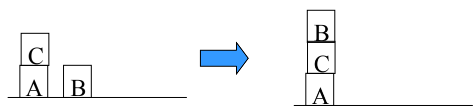
1. Assume we want to satisfy $On(A,B)$ first



Initial state

But now we cannot satisfy $On(B,C)$ without undoing $On(A,B)$

2. Assume we want to satisfy $On(B,C)$ first.



Initial state

But now we cannot satisfy $On(A,B)$ without undoing $On(B,C)$