

Informatics 2D – Reasoning and Agents Semester 2, 2011-12

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adapted from slides by Michael Rovatsos

Where are we?

The first two blocks of the course dealt with ...

- ▶ Basic notions of agency
- ▶ Intelligent problem-solving
- ▶ Heuristic search, constraints
- ▶ Logic & logical reasoning
- ▶ Reasoning about actions and time

In the remainder of the course we will talk about ...

- ▶ Planning
- ▶ Uncertainty

What is planning?

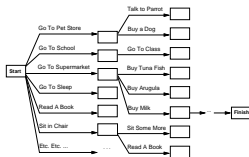
- ▶ **Planning** is the task of coming up with a sequence of actions that will achieve a goal
- ▶ We are only considering **classical planning** in which environments are
 - ▶ fully observable (accessible),
 - ▶ deterministic,
 - ▶ finite,
 - ▶ static (up to agents' actions),
 - ▶ discrete (in actions, states, objects and events).
- ▶ (Lifting some of these assumptions will be the subject of the "uncertainty" part of the course)

Why planning?

- ▶ So far we have dealt with two types of agents:
 1. Search-based problem-solving agents
 2. Logical planning agents
- ▶ Do these techniques work for solving planning problems?

Why planning?

- ▶ Consider a search-based problem-solving agent in a robot shopping world
- ▶ Task: Go to the supermarket and get milk, bananas and a cordless drill
- ▶ What would a search-based agent do?



Problems with search

- ▶ No goal-directedness.
- ▶ No problem decomposition into sub-goals that build on each other
 - ▶ May undo past achievements
 - ▶ May go to the store 3 times!
- ▶ Simple goal test doesn't allow for the identification of milestones
- ▶ How do we find a good heuristic function?
How do we model the way humans perceive complex goals and the quality of a plan?

How about logic & deductive inference?

- ▶ Generally a good idea, allows for "opening up" representations of states, actions, goals and plans
- ▶ If $Goal = Have(Bananas) \wedge Have(Milk)$ this allows achievement of sub-goals (if independent)
- ▶ Current state can be described by properties in a compact way (e.g. $Have(Drill)$ stands for hundreds of states)
- ▶ Allows for compact description of actions, for example

$$Object(x) \Rightarrow Can(a, Grab(x))$$

- ▶ Allows for representing a plan hierarchically, e.g. $GoTo(Supermarket) = Leave(House) \wedge ReachLocationOf(Supermarket) \wedge Enter(Supermarket)$ then decompose further into sub-plans

How about logic & deductive inference?

- ▶ **Problems:**
 1. In its general form either awkward (propositional logic) or tractability problems (first-order logic), high complexity
 2. If p is a sequence that achieves the goal, then so is $[a, a^{-1}|p]$
- ▶ **Solutions:** We need
 1. To reduce complexity to allow scaling up.
 2. To allow reasoning to be guided by plan 'quality'/efficiency.
- ▶ Do 1. today; 2. next time.

Representing planning problems

- ▶ Need a language expressive enough to cover interesting problems, restrictive enough to allow efficient algorithms.
- ▶ **Planning Domain Definition Language** or **PDDL**
- ▶ PDDL will allow you to express:
 1. states
 2. actions: a description of transitions between states
 3. and goals: a (partial) description of a state.

Representing States and Goals in PDDL

- ▶ **States** represented as conjunctions of propositional or function-free first order positive literals:
 - ▶ $Happy \wedge Sunshine,$
 $At(Plane_1, Melbourne) \wedge At(Plane_2, Sydney)$
- ▶ So these **aren't states**:
 - ▶ $At(x, y)$ (no variables allowed),
 $Love(Father(Fred), Fred)$ (no function symbols allowed)
 $\neg Happy$ (no negation allowed).
- ▶ **Closed-world assumption!**
- ▶ A **goal** is a **partial description** of a state, and you can use negation, variables etc. to express that description.
 - ▶ $\neg Happy, At(x, SFO), Love(Father(Fred), Fred) \dots$

Actions in PDDL

$Action(Fly(p, from, to),$

$PRECOND: At(p, from) \wedge Plane(p) \wedge Airport(from) \wedge Airport(to)$

$EFFECT: \neg At(p, from) \wedge At(p, to)$

- ▶ Actually **action schemata**, as they may contain variables
- ▶ Action name and parameter list serves to identify the action
- ▶ **Precondition**: defines states in which action is **executable**:
 - ▶ Conjunction of positive and negative literals, where all variables must occur in action name.
- ▶ **Effect**: defines how literals in the input state get changed (anything not mentioned stays the same).
 - ▶ Conjunction of positive and negative literals, with all its variables also in the preconditions.
 - ▶ Often positive and negative effects are divided into **add list** and **delete list**

The semantics of PDDL: States and their Descriptions

- ▶ $s \models At(P_1, SFO)$ iff $At(P_1, SFO) \in s$
- $s \models \neg At(P_1, SFO)$ iff $At(P_1, SFO) \notin s$
- $s \models \phi(x)$ iff there is a ground term d such that $s \models \phi[x/d]$.
- $s \models \phi \wedge \psi$ iff $s \models \phi$ and $s \models \psi$

The Semantics of PDDL: Applicable Actions

- ▶ Any action is **applicable** in any state that satisfies the precondition with an appropriate substitution for parameters.
- ▶ Example: State

$$At(P_1, Melbourne) \wedge At(P_2, Sydney) \wedge Plane(P_1) \wedge Plane(P_2) \\ \wedge Airport(Sydney) \wedge Airport(Melbourne) \wedge Airport(Heathrow)$$

satisfies

$$At(p, from) \wedge Plane(p) \wedge Airport(from) \wedge Airport(to)$$

with substitution (among others)

$$\{p/P_2, from/Sydney, to/Heathrow\}$$

The semantics of PDDL: The Result of an Action

- ▶ **Result** of executing action a in state s is state s' with any positive literal P in a 's EFFECTS added to the state and every negative literal $\neg P$ removed from it (under the given substitution) .
- ▶ In our example s' would be

$$At(P_1, Melbourne) \wedge At(P_2, Heathrow) \wedge Plane(P_1) \wedge Plane(P_2) \\ \wedge Airport(Sydney) \wedge Airport(Melbourne) \wedge Airport(Heathrow)$$

- ▶ "PDDL assumption": every literal not mentioned in the effect remains unchanged (cf. frame problem)
- ▶ **Solution** = action sequence that leads from the initial state to a state that satisfies the goal.

Blocks world example

- ▶ Given: A set of cube-shaped blocks sitting on a table
- ▶ Can be stacked, but only one on top of the other
- ▶ Robot arm can move around blocks (one at a time)
- ▶ Goal: to stack blocks in a certain way
- ▶ Formalisation in PDDL:
 - ▶ $On(b, x)$ to denote that block b is on x (block/table)
 - ▶ $Move(b, x, y)$ to indicate action of moving b from x to y
 - ▶ Precondition for this action: nothing must be stacked on x : $Clear(x)$.

Blocks world example

- ▶ Action schema:

$$Action(Move(b, x, y),$$

$$PRECOND: On(b, x) \wedge Clear(b) \wedge Clear(y)$$

$$EFFECT: On(b, y) \wedge Clear(x) \wedge \neg On(b, x) \wedge \neg Clear(y))$$
- ▶ Problem: when $x = Table$ or $y = Table$ we infer that the table is clear when we have moved a block from it (not true) and require that table is clear to move something on it (not true)
- ▶ Solution: introduce another action

$$Action(MoveToTable(b, x),$$

$$PRECOND: On(b, x) \wedge Clear(b)$$

$$EFFECT: On(b, Table) \wedge Clear(x) \wedge \neg On(b, x))$$

Does this Work?

- ▶ Interpret $Clear(b)$ as “there is space on b to hold a block” (thus $Clear(Table)$ is always true)
- ▶ But without further modification, planner can still use $Move(b, x, Table)$:
 - ▶ Needlessly increases search space (not a big problem here, but can be)
- ▶ So part of solution is to also add $Block(b) \wedge Block(y)$ to precondition of $Move$

Summary

- ▶ Defined the planning problem
- ▶ Discussed problems with search/logic
- ▶ Introduced PDDL: a special representation language for planning
- ▶ Blocks world example as a famous application domain
- ▶ Next time: Algorithms for planning!
State-Space Search and Partial-Order Planning