

The background features a large, faint watermark of the Brown University crest. The crest includes a sun with a face, a shield with a red cross, and a banner at the bottom with the Latin motto "IN DEO SPERAMUS".

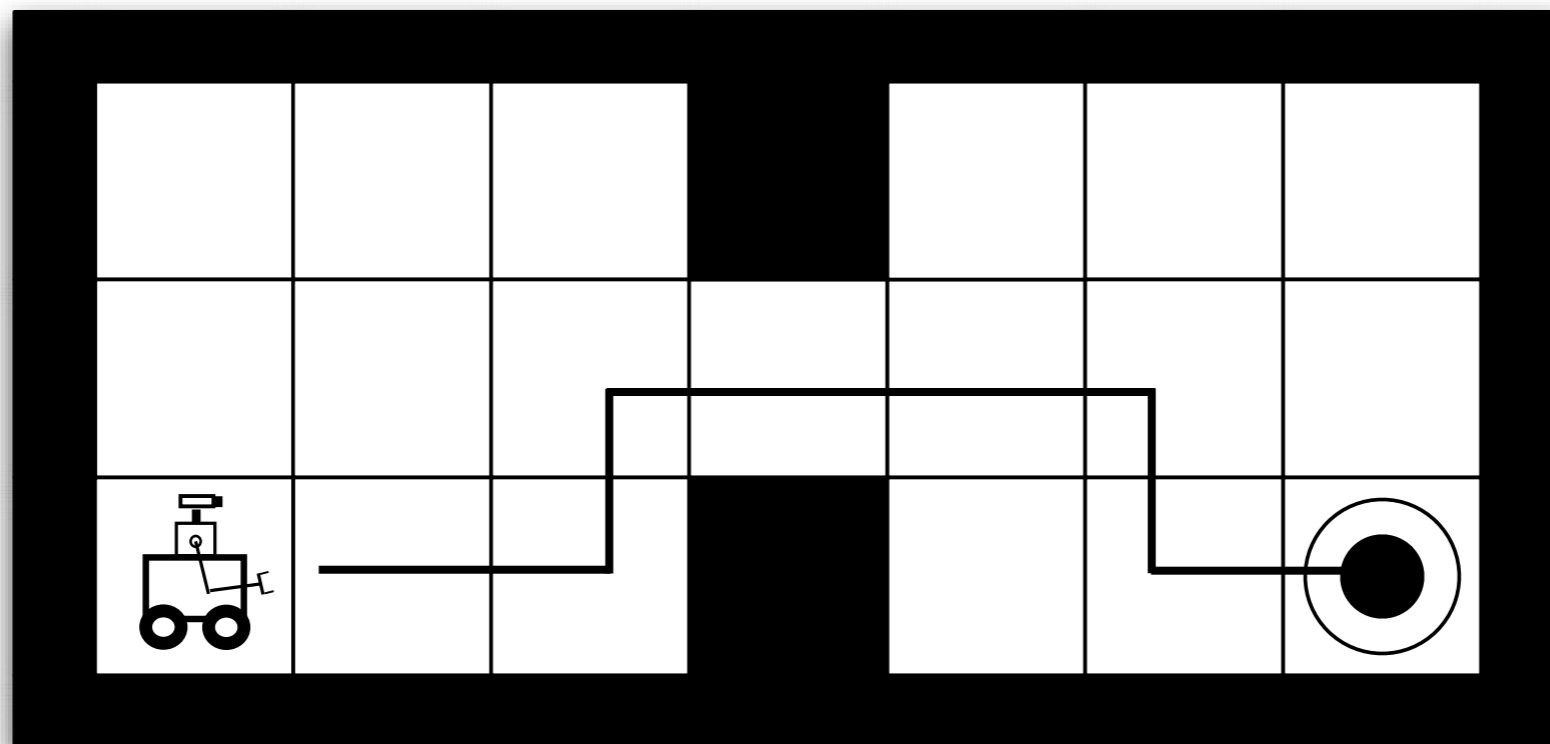
Planning

George Konidakis
gdk@cs.brown.edu

Spring 2017

The Planning Problem

Finding a sequence of actions to achieve some goal.



Planning

Fundamental to AI:

- Intelligence is about behavior.

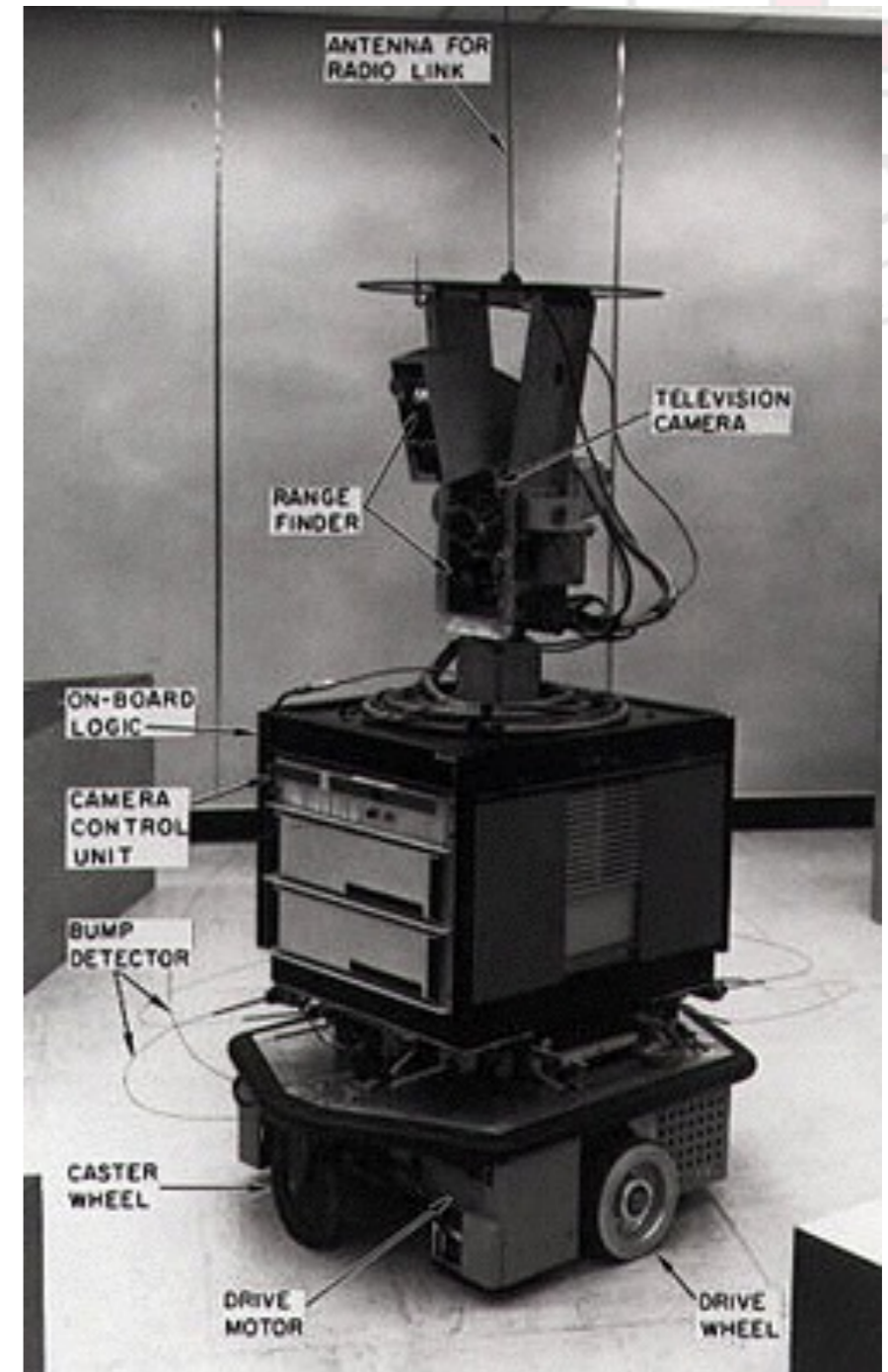


Shakey the Robot

Research project started in 1966.

Integrated:

- Computer vision.
- Planning.
- Control.
- Decision-Making.
- KRR



STRIPS Planning

Represent the world using a KB of first-order logic.

Actions can change what is currently true.

Describe the actions available:

- Preconditions
- Effects

must be true in KB

change to KB after execution



PDDL

Planning Domain Description Language

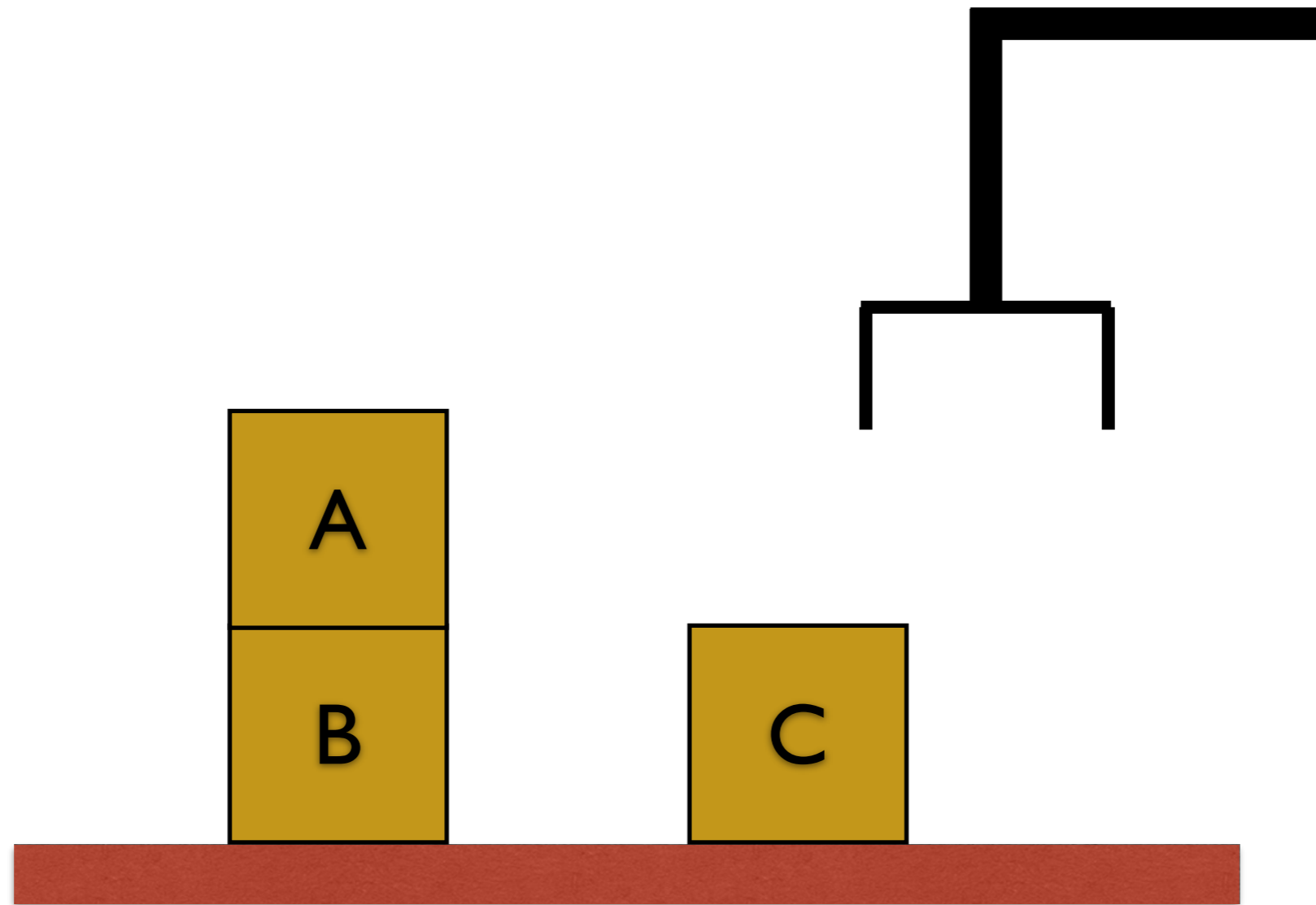
- Standard language for planning domains
- International programming competitions
- At version 3, quite complex.

Separate definitions of:

- A domain, which describes a class of tasks.
 - Predicates and operators.
- A task, which is an instance of domain.
 - Objects.
 - Start and goal states.



Examples: Blocks World



PDDL: Predicates

Predicate is a first-order logic function returning *True* or *False*, given a set of objects.

```
(define (domain blocksworld)
  (:requirements :strips :equality)
  (:predicates (clear ?x)
               (on-table ?x)
               (arm-empty)
               (holding ?x)
               (on ?x ?y)))
```

(example PDDL code from PDDL4J open source project)



PDDL: Operators

Operators:

- Name
- Parameters
- Preconditions
- Effects

(:action pickup

:parameters (?ob)

:precondition (and (clear ?ob) (on-table ?ob) (arm-empty))

:effect (and (holding ?ob) (not (clear ?ob)) (not (on-table ?ob))
(not (arm-empty))))



PDDL: Operators

(:action putdown

:parameters (?ob)

:precondition (and (holding ?ob))

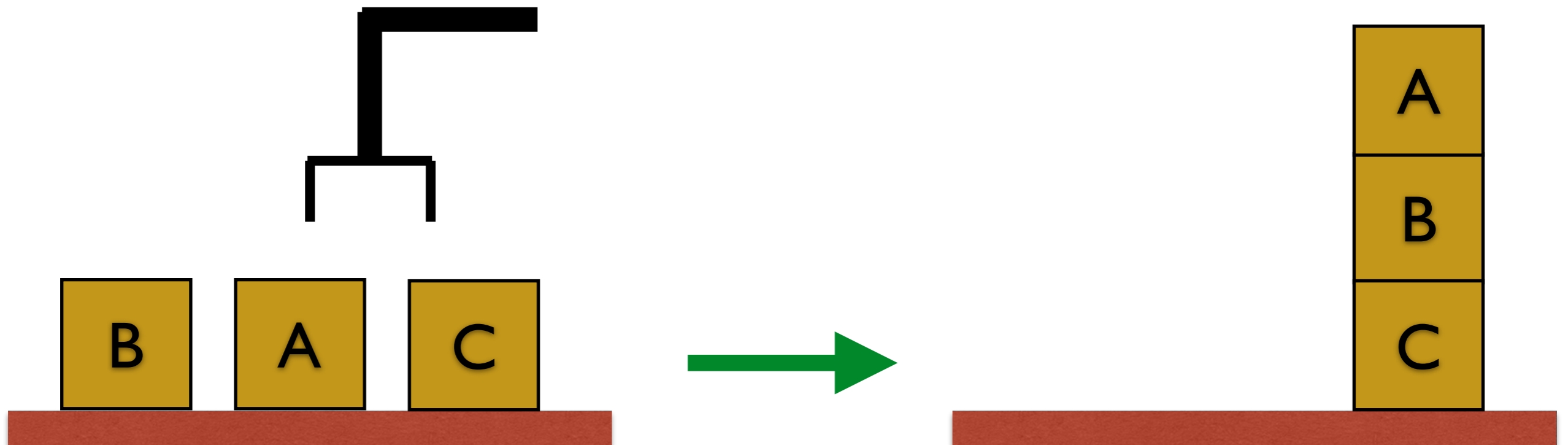
:effect (and (clear ?ob) (arm-empty) (on-table ?ob)
(not (holding ?ob))))



Note! Markov assumption.

PDDL:A Problem

```
(define (problem pb3)
  (:domain blocksworld)
  (:objects a b c)
  (:init (on-table a) (on-table b) (on-table c)
         (clear a) (clear b) (clear c) (arm-empty))
  (:goal (and (on a b) (on b c))))
```



PDDL: States

As in HMMs, state describes the configuration of the world *at a moment in time*.

Conjunction of *positive literal predicates*.

- (on-table a) (on-table b) (on-table c) (clear a) (clear b) (clear c) (arm-empty))

Those not mentioned *assumed to be False*.
(closed world assumption)

c.f. Knowledge base concept of a *model*.



PDDL: Goals

Conjunction of literal predicates:

- (and (on a b) (on b c)))

Predicates not listed are *don't-cares*.

Each goal is thus *a partial state expression*.



PPDL: Action Execution



Start state:

(on-table a) (on-table b) (on-table c)
(clear a) (clear b) (clear c) (arm-empty)

Action: pickup(a)

- Check preconditions
- Delete negative effects.
- Add positive effects.

```
(:action pickup
:parameters (?ob)
:precondition (and (clear ?ob) (on-table ?ob) (arm-empty))
:effect (and (holding ?ob) (not (clear ?ob)) (not (on-table ?ob))
(not (arm-empty))))
```

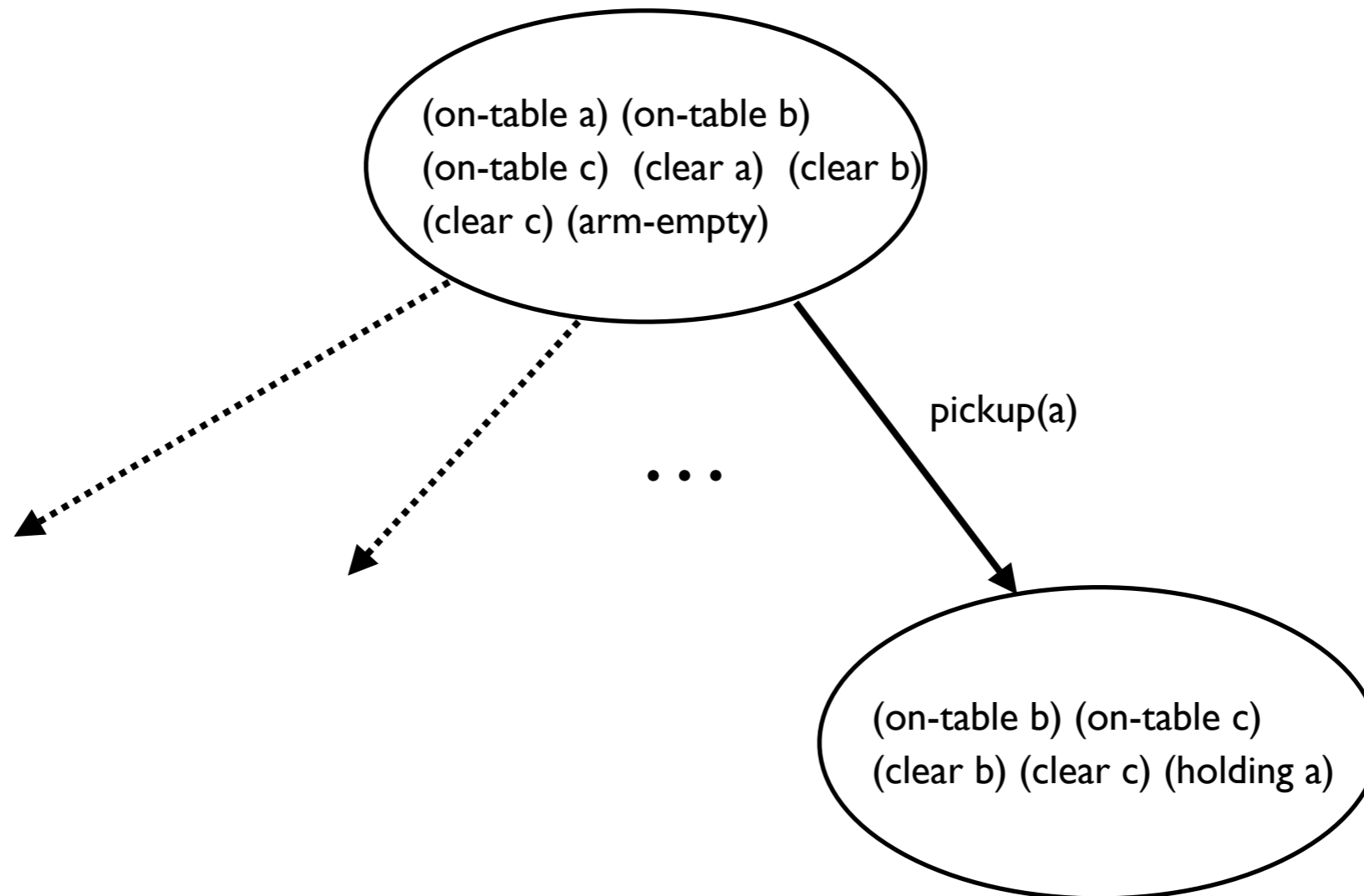
Next state:

~~(on-table a)~~ (on-table b) (on-table c)
~~(clear a)~~ (clear b) (clear c) ~~(arm-empty)~~
(holding a)

Planning

Search problem.

- Nodes are states.
- Actions are applicable operators.
- Goal expression is goal test.



Forward Search

Breadth- or depth-first search typically hopeless (high b , d)

Can use structure in the problem to build a heuristic:

- States are conjunctions of predicates.
- We know the goal predicates.
- We know the predicates deleted and added by actions.

Major approach to solving planning problems:

- *Use this knowledge to construct a problem-specific heuristic automatically.*



FFPlan

Relaxation

- Make the problem easier (e.g., delete negative effects)
- Solve the easier problem
- Use distances as a heuristic to the hard problem.
- *FF planner* (major breakthrough, circa 2001)

(:action pickup

:parameters (?ob)

:precondition (and (clear ?ob) (on-table ?ob) (arm-empty))

:effect (and (holding ?ob) ~~(not (clear ?ob))~~ ~~(not (on-table ?ob))~~

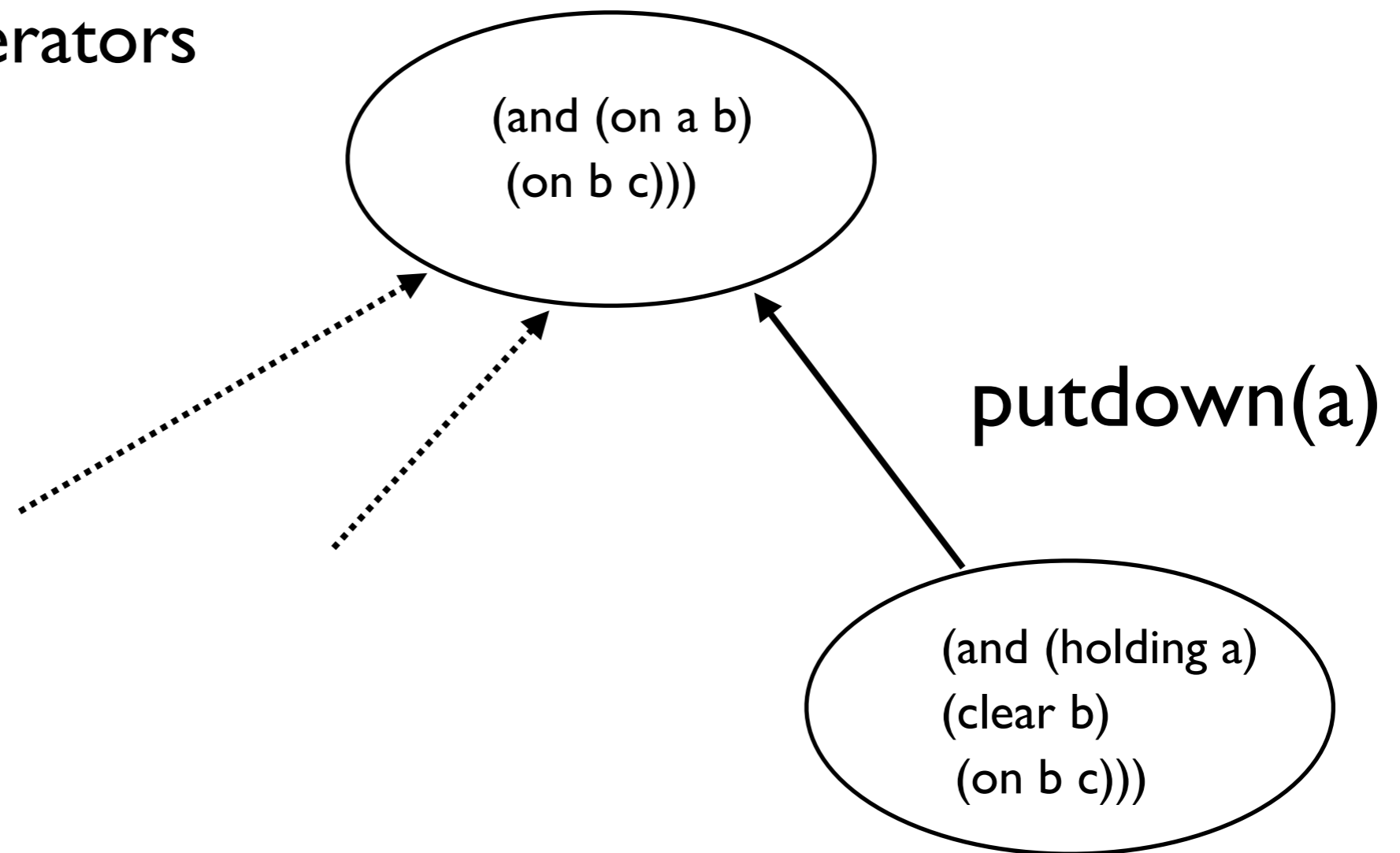
~~(not (arm-empty))))~~



Alternative Approach

Regression Planning

- Start at the goal (partial state)
- Regress backwards
- Reverse operators



Planning Competitions

Competitions held every few years

- Int. Conf. Automation and Planning
- Problems described in PDDL



IPC quality SCORE

	Tetris	Barman	Cave	Childsnack	Citycar	Floortile	Hiking	Maintenance	Openstacks	Parking	Thoughtful	Transport	Visitall	GED	Total
ibacop2	4,02	16,38	7,00	14,98	6,95	18,23	18,04	16,71	5,15	5,28	15,75	7,01	13,32	17,40	166,21
ibacop	6,28	16,27	7,00	15,29	7,32	15,18	18,65	16,81	3,58	1,74	13,76	9,94	14,18	16,73	162,73
mercury	14,38	13,94	3,00	0,00	3,99	2,00	16,46	5,06	19,69	15,64	0,00	20,00	19,88	19,01	153,04
miplan	7,46	16,54	7,00	18,22	4,69	4,10	18,14	16,62	9,07	11,08	11,18	0,00	8,18	17,72	150,00
jasper	9,52	19,78	8,00	0,00	8,89	2,00	17,19	9,28	17,28	12,91	0,00	7,59	15,18	17,27	144,89
uniform	11,52	17,83	7,00	1,23	12,74	1,53	17,01	9,36	10,83	9,74	0,00	9,25	19,56	15,65	143,25
cedalion	3,20	16,85	7,00	0,71	7,71	7,98	18,74	14,15	17,08	4,29	0,00	5,14	19,49	15,01	137,34
arvandherd	14,63	18,12	7,00	5,57	19,39	2,00	19,00	13,17	14,22	0,69	0,00	4,53	0,68	18,09	137,10
fdss-2014	9,87	11,64	7,00	1,36	5,00	2,00	17,44	16,63	17,63	10,86	0,00	4,06	8,78	15,61	127,89
dpmplan	1,80	16,57	7,00	18,46	5,82	1,97	16,28	15,07	10,15	0,00	13,18	0,00	3,41	15,79	125,50
use	3,76	15,12	0,00	0,00	1,65	9,17	8,79	15,03	15,76	3,65	0,00	6,27	14,80	13,15	107,14
nucelar	6,60	15,89	7,00	3,66	7,49	3,37	17,24	16,63	2,73	1,41	0,00	0,00	3,38	16,02	101,44
rpt	9,41	0,00	3,00	2,98	3,11	19,30	17,35	10,82	10,61	4,70	0,00	3,57	0,06	13,33	98,25
bfs-f	11,03	8,89	7,94	0,00	0,00	9,71	2,00	7,72	0,00	19,94	5,00	3,57	18,99	1,33	96,11
bifd	8,67	0,62	3,00	1,16	3,16	19,30	15,25	7,83	5,76	5,38	0,00	3,52	0,00	13,33	86,99
dae_yahsp	0,00	0,35	0,00	9,36	0,00	0,46	8,12	0,00	0,00	0,00	17,10	9,02	17,26	2,52	64,19
freelunch	3,74	0,00	3,00	17,43	0,00	7,52	1,91	15,26	9,82	0,00	0,00	0,02	2,51	0,00	61,21
yahsp3-mt	0,67	6,60	0,00	0,00	0,00	1,22	3,81	0,00	0,00	1,37	14,42	10,74	10,73	8,94	58,50
yahsp3	0,54	1,33	0,00	0,00	0,00	1,09	4,80	0,00	0,00	0,00	6,93	8,03	17,08	8,31	48,11
planets	0,00	0,00	5,97	0,00	3,96	1,00	0,77	0,00	0,00	0,00	13,25	0,00	0,00	0,00	24,95

2014 (deterministic)

DART

Planner used by the US military for logistics.

“Introduced in 1991, DART had by 1995 offset the monetary equivalent of all funds DARPA had channeled into AI research for the previous 30 years combined.”

“Directly following its launch, DART solved several logistical nightmares, saving the military millions of dollars. Military planners were aware of the tremendous obstacles facing moving military assets from bases in Europe to prepared bases in Saudi Arabia, in preparation for Desert Storm. DART quickly proved its value by improving upon existing plans of the U.S. military. What surprised many observers was DART's ability to adapt plans rapidly in a crisis environment.”

(wikipedia)

