Principles of AI Planning

4. PDDL

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1 Schematic operators

- Schematic operators
Schematic operators

- Description of state variables and operators in terms of a given finite set of objects.
- Analogy: propositional logic vs. predicate logic
- Planners take input as schematic operators and translate them into (ground) operators. This is called grounding.
Schematic operators: example

Schematic operator \texttt{drive\_car\_from\_to}(x, y_1, y_2):

\[
x \in \{\text{car1, car2}\},
\]
\[
y_1 \in \{\text{Freiburg, Strasbourg}\},
\]
\[
y_2 \in \{\text{Freiburg, Strasbourg}\}
\]
\[
\langle \text{in}(x, y_1), \text{in}(x, y_2) \land \neg \text{in}(x, y_1) \rangle
\]

corresponds to the operators

\[
\langle \text{in}(\text{car1, Freiburg}), \text{in}(\text{car1, Strasbourg}) \land \neg \text{in}(\text{car1, Freiburg}) \rangle,
\]
\[
\langle \text{in}(\text{car1, Strasbourg}), \text{in}(\text{car1, Freiburg}) \land \neg \text{in}(\text{car1, Strasbourg}) \rangle,
\]
\[
\langle \text{in}(\text{car2, Freiburg}), \text{in}(\text{car2, Strasbourg}) \land \neg \text{in}(\text{car2, Freiburg}) \rangle,
\]
\[
\langle \text{in}(\text{car2, Strasbourg}), \text{in}(\text{car2, Freiburg}) \land \neg \text{in}(\text{car2, Strasbourg}) \rangle,
\]

plus four operators that are never applicable (inconsistent change set!) and can be ignored, like

\[
\langle \text{in}(\text{car1, Freiburg}), \text{in}(\text{car1, Freiburg}) \land \neg \text{in}(\text{car1, Freiburg}) \rangle.
\]
Schematic operators: quantification

Existential quantification (for formulae only)
Finite disjunctions $\varphi(a_1) \lor \cdots \lor \varphi(a_n)$ represented as
$\exists x \in \{a_1, \ldots, a_n\} : \varphi(x)$.

Universal quantification (for formulae and effects)
Finite conjunctions $\varphi(a_1) \land \cdots \land \varphi(a_n)$ represented as
$\forall x \in \{a_1, \ldots, a_n\} : \varphi(x)$.

Example
$\exists x \in \{A, B, C\} : in(x, \text{Freiburg})$ is a short-hand for
$in(A, \text{Freiburg}) \lor in(B, \text{Freiburg}) \lor in(C, \text{Freiburg})$. 
2 PDDL

- Overview
- Domain files
- Problem files
- Example
PDDL: the Planning Domain Definition Language

- used by almost all implemented systems for deterministic planning
- supports a language comparable to what we have defined above (including schematic operators and quantification)
- syntax inspired by the Lisp programming language: e.g. prefix notation for formulae

\[(\text{and } (\text{or } (\text{on } A \ B) (\text{on } A \ C))) \]
\[(\text{or } (\text{on } B \ A) (\text{on } B \ C))\]
\[(\text{or } (\text{on } C \ A) (\text{on } A \ B))\]
A domain file consists of

- (define (domain DOMAINNAME)
- a :requirements definition (use :strips :typing by default)
- definitions of types (each parameter has a type)
- definitions of predicates
- definitions of operators
Example: blocks world (with hand) in PDDL

Note: Unlike in the previous chapter, here we use a variant of the blocks world domain with an explicitly modeled gripper/hand.

(define (domain BLOCKS)
  (:requirements :strips :typing)
  (:types block)
  (:predicates (on ?x - block ?y - block)
    (ontable ?x - block)
    (clear ?x - block)
    (handempty)
    (holding ?x - block)
  )
PDDL: operator definition

- (:action OPERATORNAME)
- list of parameters: (?x - type1 ?y - type2 ?z - type3)
- precondition: a formula

```
<schematic-state-var>
(and <formula> ... <formula>)
(or <formula> ... <formula>)
(not <formula>)
(forall (?x1 - type1 ... ?xn - typen) <formula>)
(exists (?x1 - type1 ... ?xn - typen) <formula>)
```
effect:

<schematic-state-var>
(not <schematic-state-var>)
(and <effect> ... <effect>)
(when <formula> <effect>)
(forall (?x1 - type1 ... ?xn - typen) <effect>)
(:action stack
  :parameters (?x - block ?y - block)
  :precondition (and (holding ?x) (clear ?y))
  :effect (and (not (holding ?x))
    (not (clear ?y))
    (clear ?x)
    (handempty)
    (on ?x ?y)))
A problem file consists of

- (define (problem PROBLEMNAME))
  declaration of which domain is needed for this problem
- definitions of objects belonging to each type
- definition of the initial state (list of state variables initially true)
- definition of goal states (a formula like operator precondition)
(define (problem example)
  (:domain BLOCKS)
  (:objects a b c d - block)
  (:init (clear a) (clear b) (clear c) (clear d)
        (ontable a) (ontable b) (ontable c)
        (ontable d) (handempty))
  (:goal (and (on d c) (on c b) (on b a)))
)
Fast Downward is the state-of-the-art planner, usable both for research and applications.

Main developers:
- Malte Helmert
- Gabi Röger
- Erez Karpas
- Jendrik Seipp
- Silvan Sievers
- Florian Pommerening
Fast Downward is available at
http://www.fast-downward.org/

**Installation:**
Follow instructions at
http://www.fast-downward.org/
ObtainingAndRunningFastDownward

**Running:**
Follow instructions at
http://www.fast-downward.org/PlannerUsage
Example run of Fast Downward

```bash
# ./fast-downward.py --plan-file plan.txt \ 
domain.pddl problem.pddl --search "astar(blind())"

[...] INFO Running search.
[...] Solution found!
[...] Plan length: 6 step(s).
[...] Expanded 85 state(s).
[...] Search time: 0s
[...]
Example plan found by Fast Downward

```
# cat plan.txt
(pick-up b)
(stack b a)
(pick-up c)
(stack c b)
(pick-up d)
(stack d c)
; cost = 6 (unit cost)
```
Example: blocks world in PDDL

(define (domain BLOCKS)
  (:requirements :strips :typing)
  (:types block)
  (:predicates (on ?x - block ?y - block)
    (ontable ?x - block)
    (clear ?x - block)
    (handempty)
    (holding ?x - block)
  )
)
(:action pick-up
  :parameters (?x - block)
  :precondition (and (clear ?x) (ontable ?x)
                   (handempty))
  :effect (and (not (ontable ?x))
               (not (clear ?x))
               (not (handempty))
               (holding ?x)))
(:action put-down
  :parameters (?x - block)
  :precondition (holding ?x)
  :effect (and (not (holding ?x))
            (clear ?x)
            (handempty)
            (ontable ?x)))
(:action stack
  :parameters (?x - block ?y - block)
  :precondition (and (holding ?x) (clear ?y))
  :effect (and (not (holding ?x))
            (not (clear ?y))
            (clear ?x)
            (handempty)
            (on ?x ?y)))
(:action unstack
   :parameters (?x - block ?y - block)
   :precondition (and (on ?x ?y) (clear ?x)
                   (handempty))
   :effect (and (holding ?x)
                (clear ?y)
                (not (clear ?x))
                (not (handempty))
                (not (on ?x ?y))))
(define (problem example)
  (:domain BLOCKS)
  (:objects a b c d - block)
  (:init (clear a) (clear b) (clear c) (clear d)
         (ontable a) (ontable b) (ontable c)
         (ontable d) (handempty))
  (:goal (and (on d c) (on c b) (on b a)))
)