Motivation

- We now know the basics of classical planning.
- Where to go from here? Possible routes:
  - Algorithms: techniques orthogonal to heuristic search
    (partial-order reduction, symmetry reduction, decompositions, …)
    → later
  - Algorithms: techniques other than heuristic search
    (SAT/SMT planning, …)
    → beyond the scope of this course
  - Settings beyond classical planning (nondeterminism, partial observability, numeric planning, …)
    → later
  - A slight extension to the expressiveness of classical planning tasks
    → this chapter

What are State-Dependent Action Costs?

Action costs: unit — constant — state-dependent

- cost(fly(Madrid, London)) = 1,    cost(fly(Paris, London)) = 1,
- cost(fly(Freiburg, London)) = 1,    cost(fly(Istanbul, London)) = 1.
Why Study State-Dependent Action Costs?

- In classical planning: actions have unit costs.
  - Each action $a$ costs 1.
- Simple extension: actions have constant costs.
  - Each action $a$ costs some $cost_a \in \mathbb{N}$.
  - Example: Flying between two cities costs amount proportional to distance.
  - Still easy to handle algorithmically, e.g. when computing $g$ and $h$ values.
- Further extension: actions have state-dependent costs.
  - Each action $a$ has cost function $cost_a : S \rightarrow \mathbb{N}$.
  - Example: Flying to a destination city costs amount proportional to distance, depending on the current city.

Handling State-Dependent Action Costs

Good news:
- Computing $g$ values in forward search still easy.
  (When expanding state $s$ with action $a$, we know $cost_a(s)$.)

Challenge:
- But what about SDAC-aware $h$ values
  (relaxation heuristics, abstraction heuristics)?
- Or can we simply compile SDAC away?

This chapter:
- Proposed answers to these challenges.
State-Dependent Action Costs

**Definition**
A SAS$^*$ planning task with state-dependent action costs or SDAC planning task is a tuple $\Pi = \langle V, I, O, \gamma, (\text{cost}_a)_{a \in O} \rangle$ where $(V, I, O, \gamma)$ is a (regular) SAS$^*$ planning task with state set $S$ and $\text{cost}_a : S \rightarrow \mathbb{N}$ is the cost function of $a$ for all $a \in O$.

**Assumption:** For each $a \in O$, the set of variables occurring in the precondition of $a$ is disjoint from the set of variables on which the cost function $\text{cost}_a$ depends.

(Question: Why is this assumption unproblematic?)

Definitions of plans etc. stay as before. A plan is optimal if it minimizes the sum of action costs from start to goal.

For the rest of this chapter, we consider the following running example.

<table>
<thead>
<tr>
<th>December 16th, 2016</th>
<th>B. Nebel, R. Mattmüller – AI Planning</th>
</tr>
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<tbody>
<tr>
<td>9 / 76</td>
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State-Dependent Action Costs

**Compilations**

Different ways of compiling SDAC away:
- Compilation I: “Parallel Action Decomposition”
- Compilation II: “Purely Sequential Action Decomposition”
- Compilation III: “EVMDD-Based Action Decomposition” (combination of Compilations I and II)

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9 / 76

State-Dependent Action Costs

**Running Example**

**Example (Household domain)**

**Actions:**
- $\text{vacuumFloor} = \langle \top, \text{floorClean} \rangle$
- $\text{washDishes} = \langle \top, \text{dishesClean} \rangle$
- $\text{doHousework} = \langle \top, \text{floorClean} \land \text{dishesClean} \rangle$

**Cost functions:**
- $\text{cost}_{\text{vacuumFloor}} = [\neg \text{floorClean}] \cdot 2$
- $\text{cost}_{\text{washDishes}} = [-\text{dishesClean}] \cdot (1 + 2 \cdot [-\text{haveDishwasher}])$
- $\text{cost}_{\text{doHousework}} = \text{cost}_{\text{vacuumFloor}} + \text{cost}_{\text{washDishes}}$

(Question: How much can applying action washDishes cost?)

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9 / 76

State-Dependent Action Costs

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9 / 76

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9 / 76

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9 / 76

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9 / 76

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State-Dependent Action Costs
Compilation I: “Parallel Action Decomposition”

Compilation I
Transform each action into multiple actions:
- one for each partial state relevant to cost function
- add partial state to precondition
- use cost for partial state as constant cost

Properties:
✓ always possible
✗ exponential blow-up

Question: Exponential blow-up avoidable? → Compilation II

State-Dependent Action Costs
Compilation II: “Purely Sequential Action Decomposition”

Compilation II
If costs are additively decomposable:
- high-level actions ≈ macro actions
- decompose into sequential micro actions

Properties:
✓ linear blow-up
✗ not always possible
- plan lengths not preserved
E.g., in a state where ¬fC and ¬dC hold, an application of doHousework
in the SDAC setting is replaced by an application of the action sequence

doHousework₁(¬fC), doHousework₂(¬dC)
in the compiled setting.
Properties (ctd.):
- plan costs preserved
- blow-up in search space
  E.g., in a state where \( \neg fC \) and \( \neg dC \) hold, should we apply `doHousework(\( \neg fC \))` or `doHousework(\( \neg dC \))` first?
  \( \Rightarrow \) impose action ordering!
- attention: we should apply all partial effects at end!
  Otherwise, an effect of an earlier action in the compilation might affect the cost of a later action in the compilation.

Question: Can this always work (kind of)? \( \Rightarrow \) Compilation III

Example (ctd.)

`cost_{doHousework} = [\neg floorClean] \cdot 2 + [\neg dishesClean] \cdot (1 + 2 \cdot [\neg haveDishwasher])`

Simplify right-hand part of diagram:
- Branch over single variable at a time.
- Exploit: `haveDishwasher` irrelevant if `dishesClean` is true.

Later:
- Compiled actions
- Auxiliary variables to enforce action ordering

Compilation III
- exploit as much additive decomposability as possible
- multiply out variable domains where inevitable
- Technicalities:
  - fix variable ordering
  - perform Shannon and isomorphism reduction (cf. theory of BDDs)

Properties:
- always possible
- worst-case exponential blow-up, but as good as it gets
- as with Compilation II: plan lengths not preserved, plan costs preserved
- as with Compilation II: action ordering, all effects at end!
State-Dependent Action Costs
Compilation III: “EVMDD-Based Action Decomposition”

Compilation III provides optimal combination of sequential and parallel action decomposition, given fixed variable ordering.

Question: How to find such decompositions automatically?

Answer: Figure for Compilation III basically a reduced ordered edge-valued multi-valued decision diagram (EVMDD)!

[Lai et al., 1996; Ciardo and Siminiceanu, 2002]

EVMDDs
Edge-Valued Multi-Valued Decision Diagrams

EVMDDs:
- Decision diagrams for arithmetic functions
- Decision nodes with associated decision variables
- Edge weights: partial costs contributed by facts
- Size of EVMDD compact in many “typical”, well-behaved cases (Question: For example?)

Properties:
- ✓ satisfy all requirements for Compilation III, even (almost) uniquely determined by them
- ✓ already have well-established theory and tool support
- ✓ detect and exhibit additive structure in arithmetic functions

Consequence:
- represent cost functions as EVMDDs
- exploit additive structure exhibited by them
- draw on theory and tool support for EVMDDs

Two perspectives on EVMDDs:
- graphs specifying how to decompose action costs
- data structures encoding action costs (used independently from compilations)

Example (EVMDD Evaluation)
\[ \text{cost}_a = xy^2 + z + 2 \]
\[ D_x = D_z = \{0, 1\}, \quad D_y = \{0, 1, 2\} \]

- Directed acyclic graph
- Dangling incoming edge
- Single terminal node 0
- Decision nodes with:
  - decision variables
  - edge label
  - edge weights

We see: z independent from rest, y only matters if \( x \neq 0 \).

\[ s = \{x \mapsto 1, \quad y \mapsto 2, \quad z \mapsto 0\} \]
EVMDDs
Edge-Valued Multi-Valued Decision Diagrams

Properties of EVMDDs:
- Existence for finitely many finite-domain variables
- Uniqueness/canonicity if reduced and ordered
- Basic arithmetic operations supported

(Lai et al., 1996; Ciardo and Siminiceanu, 2002)

EVMDDs
Arithmetic operations on EVMDDs

Given arithmetic operator \( \otimes \in \{+, -, \cdot, \ldots\} \), EVMDDs \( E_1, E_2 \).
Compute EVMDD \( E = E_1 \otimes E_2 \).

Implementation: procedure apply(\( \otimes \), \( E_1 \), \( E_2 \)):
- Base case: single-node EVMDDs encoding constants
- Inductive case: apply \( \otimes \) recursively:
  - push down edge weights
  - recursively apply \( \otimes \) to corresponding children
  - pull up excess edge weights from children

Time complexity [Lai et al., 1996]:
- additive operations: product of input EVMDD sizes
- in general: exponential

EVMDD-Based Action Compilation

Idea: each edge in the EVMDD becomes a new micro action with constant cost corresponding to the edge constraint, precondition that we are currently at its start EVMDD node, and effect that we are currently at its target EVMDD node.

Example (EVMDD-based action compilation)
Let \( a = (\chi, e) \), \( \text{cost}_a = xy^2 + z + 2 \).

Auxiliary variables:
- One semaphore variable \( \sigma \) with \( D_\sigma = \{0, 1\} \) for entire planning task.
- One auxiliary variable \( \alpha = \alpha_a \) with \( D_\alpha = \{0, 1, 2, 3, 4\} \) for action \( a \).

Replace \( a \) by new auxiliary actions (similarly for other actions).
By construction.

**Proof.**

Proposition

**Proposition**

The size $|\Pi'|$ is in the order $O(|\Pi| \cdot \max_{a \in O} ||\mathcal{E}_a||)$, i.e. polynomial in the size of $\Pi$ and the largest used EVMDD.

**Proof.**

Proposition

Let $\Pi$ be an SDAC task and $\Pi' = EAC(\Pi)$ its EVMDD-based action compilation (for appropriate EVMDDs $\mathcal{E}_a$).

**Proposition**

$\Pi'$ has only state-independent costs.

**Proof.**

By construction.

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Let $\Pi$ be an SDAC task and $\Pi' = EAC(\Pi)$ its EVMDD-based action compilation (for appropriate EVMDDs $\mathcal{E}_a$).

**Proposition**

$\Pi'$ has only state-independent costs. The size $|\Pi'|$ is in the order $O(|\Pi| \cdot \max_{a \in O} ||\mathcal{E}_a||)$, i.e. polynomial in the size of $\Pi$ and the largest used EVMDD.

**Proof.**

By construction.

EVMDD-Based Action Compilation

Example (EVMDD-based action compilation, ctd.)

- $a^x = (\chi \land \sigma = 0 \land \alpha = 0), \quad cost = 2$
  - $a^1 x = (\alpha = 1 \land x = 1), \quad cost = 0$
  - $a^0 y = (\alpha = 2 \land y = 0), \quad cost = 0$
  - $a^0 z = (\alpha = 3 \land z = 0), \quad cost = 0$
  - $a^0 = (\alpha = 0), \quad cost = 0$

Let $\Pi = (V, I, O, \gamma, (cost_a)_{a \in O})$ be an SDAC planning task, and for each action $a \in O$, let $\mathcal{E}_a$ be an EVMDD that encodes the cost function $cost_a$. Let $EAC(a)$ be the set of actions created from $a$ using $\mathcal{E}_a$ similar to the previous example. Then the EVMDD-based action compilation of $\Pi$ using $\mathcal{E}_a$, $a \in O$, is the task $\Pi' = EAC(\Pi) = (V', I', O', \gamma')$, where

- $V' = V \cup \{\sigma\}$
- $I' = I \cup \{a \mapsto 0\}$
- $O' = \bigcup_{a \in O} EAC(a)$
- $\gamma' = \gamma \land (\sigma = 0) \land \land_{a \in O}(\alpha_a = 0)$.
Moreover, the sequence \( a_i^0, \ldots, a_i^{k_i} \) is applicable in \( s_{i-1} \cup \{ \sigma \mapsto 0 \} \cup \{ \alpha_i \mapsto 0 | a \in O \} \) and leads to:
\[
\begin{align*}
\text{cost} & = \text{cost}_{a_i}(s_i) + \cdots + \text{cost}_{a_i^{k_i}}(s_i) = \\
& = \text{cost}_{a_i}(s_0) + \cdots + \text{cost}_{a_i}(s_{n-1}) = \text{cost}(\pi).
\end{align*}
\]

Still to show: \( \pi' \) admits no other plans. It suffices to see that the semaphore \( \sigma \) prohibits interleaving more than one EVMDD evaluation, and that each \( \alpha_i \) makes sure that the EVMDD for \( a \) is traversed in the unique correct order.

\[\Box\]

**Example (Ctd.)**

Compilation of \( a \):

\[
a^x = (u \wedge a \wedge 0 = 0), \quad \sigma := 1 \wedge \alpha_a := 1),
\]
\[
cost = 2
\]

\[
a^1.x := (\alpha_a = 1 \wedge x = 0), \quad \alpha_a := 3),
\]
\[
cost = 0
\]

\[
a^{1}.x^+ := (\alpha_a = 1 \wedge x = 1), \quad \alpha_a := 2),
\]
\[
cost = 0
\]

\[
a^2.y := (\alpha_a = 2 \wedge y = 0), \quad \alpha_a := 3),
\]
\[
cost = 0
\]

\[
a^{2}.y^+ := (\alpha_a = 2 \wedge y = 1), \quad \alpha_a := 3),
\]
\[
cost = 1
\]

\[
a^2.y^2 := (\alpha_a = 2 \wedge y = 2), \quad \alpha_a := 3),
\]
\[
cost = 4
\]

\[
a^3.z := (\alpha_a = 3 \wedge z = 0), \quad \alpha_a := 4),
\]
\[
cost = 1
\]

\[
a^{3}.z^+ := (\alpha_a = 3 \wedge z = 1), \quad \alpha_a := 4),
\]
\[
cost = 4
\]

\[
a^4 = (\alpha_a := 4), \quad u := 1 \wedge \sigma := 0 \wedge \alpha_a := 0),
\]
\[
cost = 0
\]

Optimal plan for \( \pi' \) (with \( \text{cost}(\pi') = 6 + 1 = 7 = \text{cost}(\pi) \)):

\[
\pi' = a^x, a^{1}.x, a^2.y^2, a^3.z, a^e, b^x, b^{1}.z, b^e.
\]

\[\text{cost} = 2 + 0 + 4 + 0 + 6 = \text{cost} = 1 + 0 + 0 + 1\]

**Example (Ctd.)**

Compilation of \( b \):

\[
b^x = (u = 1 \wedge a \wedge 0 = 0), \quad \sigma := 1 \wedge \alpha_b := 1),
\]
\[
cost = 1
\]

\[
b^1.z := (\alpha_b = 1 \wedge z = 0), \quad \alpha_b := 2),
\]
\[
cost = 0
\]

\[
b^{1}.z^+ := (\alpha_b = 1 \wedge z = 1), \quad \alpha_b := 2),
\]
\[
cost = 1
\]

\[
b^2 = (\alpha_b := 2), \quad u := 2 \wedge \sigma := 0 \wedge \alpha_b := 0),
\]
\[
cost = 0
\]

Optimal plan for \( \pi' \) (with \( \text{cost}(\pi') = 6 + 1 = 7 = \text{cost}(\pi) \)):

\[
\pi' = a^x, a^{1}.x, a^2.y^2, a^3.z, a^e, b^x, b^{1}.z, b^e.
\]

\[\text{cost} = 2 + 0 + 4 + 0 + 6 = \text{cost} = 1 + 0 + 0 + 1\]
Okay. We can compile SDAC away somewhat efficiently. Is this the end of the story?
No! Why not?
- Tighter integration of SDAC into planning process might be beneficial.
- Analysis of heuristics for SDAC might improve our understanding.
- Consequence: Let’s study heuristics for SDAC in uncompiled setting.

We know: Delete-relaxation heuristics informative in classical planning.

Question: Are they also informative in SDAC planning?

Assume we want to compute the additive heuristic $h^{add}$ in a task with state-dependent action costs.
But what does an action cost in a relaxed state $s^*$?
And how to compute that cost?
Relaxed SAS* Tasks

Delete relaxation in SAS* tasks works as follows:

- Operators are already in effect normal form.
- We do not need to impose a positive normal form, because all conditions are conjunctions of facts, and facts are just variable-value pairs and hence always positive.
- Hence $a^+ = a$ for any operator $a$, and $\Pi^+ = \Pi$.
- For simplicity, we identify relaxed states $s^+$ with their on-sets on$(s^+)$.
- Then, a relaxed state $s^+$ is a set of facts $(v, d)$ with $v \in V$ and $d \in D_v$ including at least one fact $(v, d)$ for each $v \in V$ (but possibly more than one, which is what makes it a relaxed state).

Action Costs in Relaxed States

Example
Assume $s^+$ is the relaxed state with

$$s^+ = \{(x, 0), (x, 1), (y, 1), (y, 2), (z, 0)\}.$$  

What should action $a$ with $\text{cost}_a = xy^2 + z + 2$ cost in $s^+$?

Relaxed SAS* Tasks

- A relaxed operator $a$ is applicable in a relaxed state $s^+$ if all precondition facts of $a$ are contained in $s^+$.
- Relaxed states accumulate facts reached so far.
- Applying a relaxed operator $a$ to a relaxed state $s^+$ adds to $s^+$ those facts made true by $a$.

Example
Relaxed operator $a^+ = (x = 2, y := 1 \land z := 0)$ is applicable in relaxed state $s^+ = \{(x, 0), (x, 2), (y, 0), (z, 1)\}$, because precondition $(x, 2) \in s^+$, and leads to successor $(s^+)' = s^+ \cup \{(y, 1), (z, 0)\}$.

Relaxed plans, dominance, monotonicity etc. as before. The above definition generalizes the one for propositional tasks.

Action Costs in Relaxed States

Idea: We should assume the cheapest way of applying $a^+$ in $s^+$ to guarantee admissibility of $h^+$.

(Allow at least the behavior of the unrelaxed setting at no higher cost.)

Example

$$x = 0, y = 1, z = 0 \leadsto a [2]$$

$$x = 0, y = 2, z = 0 \leadsto a [2]$$

$$x = 1, y = 1, z = 0 \leadsto a [3]$$

$$x = 1, y = 2, z = 0 \leadsto a [6]$$
**Action Costs in Relaxed States**

**Idea:** We should assume the cheapest way of applying \( a^* \) in \( s^* \) to guarantee admissibility of \( h^* \).

(Allow at least the behavior of the unrelaxed setting at no higher cost.)

**Example**

\[
\begin{align*}
\text{s}^* & \rightarrow \text{a}^* [2] \\
& \rightarrow \text{t}^*
\end{align*}
\]

**Problem with this definition:** There are generally exponentially many states \( s \) consistent with \( s^* \) to minimize over.

**Central question:** Can we still do this minimization efficiently?

**Answer:** Yes, at least efficiently in the size of an EVMDD encoding \( \text{cost}_a \).

**Cost Computation for Relaxed States**

**Example**

Relaxed state \( s^* = \{(x, 0), (x, 1), (y, 1), (y, 2), (z, 0)\} \).

- Computing \( \text{cost}_a(s^*) = \min \text{cost}_a(s) \) for all \( s \) consistent with \( s^* \) = minimizing over all start-end-paths in EVMDD following only edges consistent with \( s^* \).
- **Observation:** Minimization over exponentially many paths can be replaced by top-sort traversal of EVMDD, minimizing over incoming arcs consistent with \( s^* \) at all nodes.
Cost Computation for Relaxed States

**Example**

Relaxed state $s^+ = \{(x,0),(x,1),(y,1),(y,2),(z,0)\}$.

- $\text{cost}_s(s^+) = 2$
- Cost-minimizing $s$ consistent with $s^+$: $s(x) = s(z) = 0$, $s(y) \in \{1,2\}$.

**Theorem**

A top-sort traversal of the EVMDD for $\text{cost}_s$, adding edge weights and minimizing over incoming arcs consistent with $s^+$ at all nodes, computes $\text{cost}_s(s^+)$ and takes time in the order of the size of the EVMDD.

**Proof.**

Homework?

Relaxation Heuristics

The following definition is equivalent to the RPG-based one.

**Definition (Classical additive heuristic $h^{\text{add}}$)**

$$h^{\text{add}}(s) = h^{\text{add}}_{\text{GoalFacts}}$$

$$h^{\text{add}}_{s}(\text{Facts}) = \sum_{\text{fact } \in \text{Facts}} h^{\text{add}}_{s}(\text{fact})$$

$$h^{\text{add}}_{s}(\text{fact}) = \begin{cases} 0 & \text{achieves a of fact} \\ \min_{\text{fact } \in \text{Facts}} \left[h^{\text{add}}_{s}(\text{pre}(a)) + \text{cost}_a \right] & \text{otherwise} \end{cases}$$

**Question:** How to generalize $h^{\text{add}}$ to SDAC?

Relaxations with SDAC

**Example**

- $a = \langle \top, x = 1 \rangle$ \hspace{1cm} $\text{cost}_s = 2 - 2y$
- $b = \langle \top, y = 1 \rangle$ \hspace{1cm} $\text{cost}_b = 1$

$\begin{cases} s = \{x \mapsto 0, y \mapsto 0\} \\ h_{s}^{\text{add}}(y = 1) = 1 \\ h_{s}^{\text{add}}(x = 1) = ? \end{cases}$

- cheaper!
Relaxations with SDAC

(Here, we need the assumption that no variable occurs both in the cost function and the precondition of the same action):

Definition (Additive heuristic $h^{add}$ for SDAC)

$$h^{add}_s(\text{fact}) = \begin{cases} 0 & \text{if } \text{fact} \in s \\ \min \text{achieve } a \text{ of } \text{fact} \quad [h^{add}_s(\text{pre}(a)) + \text{cost}_a] & \text{otherwise} \end{cases}$$

Let $\Pi$ be an SDAC planning task, let $\Gamma$ be an EVMDD-based action compilation of $\Pi$, and let $s$ be a state of $\Pi$. Then the classical $h^{add}$ heuristic in $\Gamma$ gives the same value for $s \cup \{ \sigma \mapsto 0 \} \cup \{ \alpha_a \mapsto 0 \ | \ a \in O \}$ as the generalization of $h^{add}$ to SDAC tasks defined above gives for $s$ in $\Pi$.

Computing $h^{add}$ for SDAC:

- Option 1: Compute classical $h^{add}$ on compiled task.
- Option 2: Compute $Cost^s_a$ directly. How?
  - Plug EVMDDs as subgraphs into RPG
  - Efficient computation of $h^{add}$

**Option 2: RPG Compilation Option 2:**

Computing $Cost^s_a$

Evaluate nodes:
- $\text{cost}_a = xy^2 + z + 2$
- Variable nodes become $\lor$-nodes
- Weights become $\land$-nodes
- Augment with input nodes
- Ensure complete evaluation
- Insert $h^{add}$ values
- $\land: \sum(\text{parents}) + \text{weight}$
- $\lor: \min(\text{parents})$
- $Cost^s_a = [h^{add}_s(\text{pre}(a))]$
Additive Heuristic

- Use above construction as subgraph of RPG in each layer, for each action (as operator subgraphs).
- Add AND nodes conjoining these subgraphs with operator precondition graphs.
- Link EVMDD outputs to next proposition layer.

Theorem
Let $\Pi$ be an SDAC planning task. Then the classical additive RPG evaluation of the RPG constructed using EVMDDs as above computes the generalized additive heuristic $h^{add}$ defined before.

Abstraction Heuristics for SDAC

Question: Why consider abstraction heuristics?

Answer:
- admissibility
- $\Rightarrow$ optimality

Abstraction Heuristics for SDAC

Question: What are the abstract action costs?

Answer: For admissibility, abstract cost of $a$ should be

$$cost_a(s^{abs}) = \min_{s \text{ concrete state } s \text{ abstracted to } s^{abs}} cost_a(s).$$

Problem: exponentially many states in minimization
Aim: Compute $cost_a(s^{abs})$ efficiently (given EVMDD for $cost_a(s)$).
Cartesian Abstractions

We will see: possible if the abstraction is Cartesian or coarser.
(Includes projections and domain abstractions.)

Definition (Cartesian abstraction)
A set of states \( s^{\text{abs}} \) is Cartesian if it is of the form \( D_1 \times \cdots \times D_n \),
where \( D_i \subseteq \mathcal{D}_i \) for all \( i = 1, \ldots, n \).
An abstraction is Cartesian if all abstract states are Cartesian sets.
[Seipp and Helmert, 2013]

Intuition: Variables are abstracted independently.
\( \xRightarrow{\text{exploit independence}} \) when computing abstract costs!

Cartesian Abstractions

Example (Cartesian abstraction)
Cartesian abstraction over \( x, y \)

Cost \( x + y + 1 \), \( \text{cost}(s^{\text{abs}}) = 2 \), local minim.: \( 1 \xrightarrow{\text{underestimate}} \)

Why does the topsort EVMDD traversal (cheapest path computation) correctly compute \( \text{cost}_{\text{ls}}(s^{\text{abs}}) \)?
Short answer: The exact same thing as with relaxed states, because relaxed states are Cartesian sets!

Longer answer:
1. For each Cartesian state \( s^{\text{abs}} \) and each variable \( v \),
each value \( d \in \mathcal{D} \) is either consistent with \( s^{\text{abs}} \) or not.
2. This implies: at all decision nodes associated with variable \( v \),
some outgoing edges are enabled, others are disabled.
   This is independent from all other decision nodes.
3. This allows local minimizations over linearly many edges
   instead of global minimization over exponentially many
   paths in the EVMDD when computing minimum costs.
\( \xRightarrow{\text{polynomial in EVMDD size}} \)

Cartesian Abstractions

Not Cartesian!
If abstraction not Cartesian: two variables can be
- independent in cost function (\( \xrightarrow{\text{compact EVMDD}} \) but
- dependent in abstraction.
\( \xrightarrow{\text{cannot consider independent parts of EVMDD separately.}} \)

Example (Non-Cartesian abstraction)
\( \text{cost}: x + y + 1 \), \( \text{cost}(s^{\text{abs}}) = 2 \), local minim.: \( 1 \xrightarrow{\text{underestimate}} \)

**Counterexample-Guided Abstraction Refinement**

**Wanted:** principled way of computing Cartesian abstractions.

⇝ Counterexample-Guided Abstraction Refinement (CEGAR)

(details omitted)

![Diagram](image)

**Practice**

**EVMDD Libraries**

**MEDDLY**

- **MEDDLY:** Multi-terminal and Edge-valued Decision Diagram Library
- **Authors:** Junaid Babar and Andrew Miner
- **Language:** C++
- **License:** open source (LGPLv3)
- **Advantages:**
  - many different types of decision diagrams
  - mature and efficient
- **Disadvantages:**
  - documentation
- **Code:** http://meddly.sourceforge.net

**pyevmdd**

- **pyevmdd:** EVMDD library for Python
- **Authors:** RM and Florian Geißer
- **Language:** Python
- **License:** open source (GPLv3)
- **Disadvantages:**
  - restricted to EVMDDs
  - neither mature nor optimized
- **Purpose:** our EVMDD playground
- **Code:** https://github.com/robertmattmueller/pyevmdd
- **Documentation:** http://pyevmdd.readthedocs.io/en/latest/
Let $a$ be a goal state.

Example (EVMDD-based action compilation)

And effect that we are currently at its target EVMDD node.

- **precondition** that we are currently at its start EVMDD node,

Idea: each edge in the EVMDD becomes a new micro action

EVMDD-Based Action Compilation

- **metric** (minimize (total-cost))

Custom syntax (non-standard PDDL):

- **Besides** :parameters, :precondition, and :effect,

actions may have field

- **:cost** (<expression>)

EVMDD-Based Action Compilation

Usual way of representing costs in PDDL:

- effects (increase (total-cost) (<expression>))

PDDL Representation

References

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Summary

State-dependent actions costs practically relevant.

EVMDDs exhibit and exploit structure in cost functions.

Graph-based representations of arithmetic functions.

Edge values express partial cost contributed by facts.

Size of EVMDD is compact in many “typical” cases.

Can be used to compile tasks with state-dependent costs
to tasks with state-independent costs.

Alternatively, can be embedded into the RPG to compute
forward-cost heuristics directly.

For $h^{add}$, both approaches give the same heuristic values.

Abstraction heuristics can also be generalized to
state-dependent action costs.

Future Work and Work in Progress:

- Investigation of other delete-relaxation heuristics for tasks
  with state-dependent action costs.
- Investigation of static and dynamic EVMDD variable
  orders.
- Application to cost partitioning, to planning with
  preferences, …
- Better integration of SDAC in PDDL.
- Tool support.
- Benchmarks.
References

