Introduction to search algorithms for planning

Search algorithms are used to find solutions (plans) for transition systems in general, not just for planning tasks.

Planning is one application of search among many.

In this chapter, we describe some popular and/or representative search algorithms, and (the basics of) how they apply to planning.

Most of this is review of material that should be known (details: Russell and Norvig’s textbook).

Our plan for the next lectures

Choices to make:

1. search direction: progression/regression/both
   → previous chapter
2. search space representation: states/sets of states
   → previous chapter
3. search algorithm: uninformed/heuristic; systematic/local
   → this chapter
4. search control: heuristics, pruning techniques
   → next chapters
Search states vs. search nodes

In search, one distinguishes:

- **search states** \( s \) – states (vertices) of the transition system
- **search nodes** \( \sigma \) – search states plus information on where/when/how they are encountered during search

What is in a search node?

Different search algorithms store different information in a search node \( \sigma \), but typical information includes:

- **state** \( \sigma \): associated search state
- **parent** \( \sigma \): pointer to search node from which \( \sigma \) is reached
- **action** \( \sigma \): action leading from state \( \text{state(parent(\sigma))} \) to state \( \text{state(\sigma)} \)
- **g** \( \sigma \): cost of \( \sigma \) (length of path from the root node)

For the root node, **parent** \( \sigma \) and **action** \( \sigma \) are undefined.

Search states vs. planning states

Search states \( \neq \) (planning) states:

- **Search states** don’t have to correspond to states in the planning sense.
- **progression**: search states \( \approx \) (planning) states
- **regression**: search states \( \approx \) sets of states (formulae)

Search algorithms for planning where search states are planning states are called **state-space search algorithms**.

Strictly speaking, regression is not an example of state-space search, although the term is often used loosely.

However, we will put the emphasis on progression, which is almost always state-space search.

Required ingredients for search

A general search algorithm can be applied to any transition system for which we can define the following three operations:

- **init()**: generate the initial state
- **is-goal(s)**: test if a given state is a goal state
- **succ(s)**: generate the set of successor states of state \( s \), along with the operators through which they are reached (represented as pairs \( \langle o, s' \rangle \) of operators and states)

Together, these three functions form a search space (a very similar notion to a transition system).

Search for planning: progression

Let \( \Pi = \langle A, I, O, \gamma \rangle \) be a planning task.

Search space for progression search

- **states**: all states of \( \Pi \) (assignments to \( A \))
- **init()** = \( I \)
- **is-goal(s)** = \( \begin{cases} \text{true} & \text{if} \ s \models \gamma \\ \text{false} & \text{otherwise} \end{cases} \)
- **succ(s)** = \( \{ \langle o, s' \rangle \mid \text{applicable} \ o \in O, s' = \text{app}_o(s) \} \)
Search for planning: regression

Let $\Pi = \langle A, I, O, \gamma \rangle$ be a planning task.

Search space for regression search

states: all formulae over $A$ (how many?)

- $\text{init}() = \gamma$
- $\text{is-goal}(\varphi) = \begin{cases} \text{true} & \text{if } I \models \varphi \\ \text{false} & \text{otherwise} \end{cases}$
- $\text{succ}(\varphi) = \{ \langle o, \varphi' \rangle \mid o \in O, \varphi' = \text{regr}_o(\varphi), \varphi' \text{ is satisfiable} \}$ (modified if splitting is used)

Classification of search algorithms

uninformed search vs. heuristic search:
- uninformed search algorithms only use the basic ingredients for general search algorithms
- heuristic search algorithms additionally use heuristic functions which estimate how close a node is to the goal

systematic search vs. local search:
- systematic algorithms consider a large number of search nodes simultaneously
- local search algorithms work with one (or a few) candidate solutions (search nodes) at a time
- not a black-and-white distinction; there are crossbreeds (e.g., enforced hill-climbing)

Classification: what works where in planning?

uninformed vs. heuristic search:
- For satisficing planning, heuristic search vastly outperforms uninformed algorithms on most domains.
- For optimal planning, the difference is less pronounced.

systematic search vs. local search:
- For satisficing planning, the most successful algorithms are somewhere between the two extremes.
- For optimal planning, systematic algorithms are required.

Common procedures for search algorithms

Before we describe the different search algorithms, we introduce three procedures used by all of them:
- make-root-node: Create a search node without parent.
- make-node: Create a search node for a state generated as the successor of another state.
- extract-solution: Extract a solution from a search node representing a goal state.
Procedure make-root-node

**make-root-node**: Create a search node without parent.

**Procedure make-root-node**

```python
def make-root-node(s):
    σ := new node
    state(σ) := s
    parent(σ) := undefined
    action(σ) := undefined
    g(σ) := 0
    return σ
```

Procedure make-node

**make-node**: Create a search node for a state generated as the successor of another state.

**Procedure make-node**

```python
def make-node(σ, o, s):
    σ' := new node
    state(σ') := s
    parent(σ') := σ
    action(σ') := o
    g(σ') := g(σ) + 1
    return σ'
```

Procedure extract-solution

**extract-solution**: Extract a solution from a search node representing a goal state.

**Procedure extract-solution**

```python
def extract-solution(σ):
    solution := new list
    while parent(σ) is defined:
        solution.push-front(action(σ))
        σ := parent(σ)
    return solution
```

Uninformed search algorithms

**Uninformed search algorithms**
Uninformed search algorithms

- Uninformed algorithms are less relevant for planning than heuristic ones, so we keep their discussion brief.
- Uninformed algorithms are mostly interesting to us because we can compare and contrast them to related heuristic search algorithms.

Popular uninformed systematic search algorithms:
- breadth-first search
- depth-first search
- iterated depth-first search

Popular uninformed local search algorithms:
- random walk

Breadth-first search without duplicate detection

```plaintext
queue := new fifo-queue
queue.push-back(make-root-node(init()))
while not queue.empty():
    σ = queue.pop-front()
    if is-goal(state(σ)):
        return extract-solution(σ)
    for each (o, s) ∈ succ(state(σ)):
        σ' := make-node(σ, o, s)
        queue.push-back(σ')
return unsolvable
```

Possible improvement: duplicate detection (see next slide).

Another possible improvement: test if σ' is a goal node; if so, terminate immediately. (We don’t do this because it obscures the similarity to some of the later algorithms.)

Breadth-first search with duplicate detection

```plaintext
queue := new fifo-queue
queue.push-back(make-root-node(init()))
closed := ∅
while not queue.empty():
    σ = queue.pop-front()
    if state(σ) ∉ closed:
        closed := closed ∪ {state(σ)}
        if is-goal(state(σ)):
            return extract-solution(σ)
        for each (o, s) ∈ succ(state(σ)):
            σ' := make-node(σ, o, s)
            queue.push-back(σ')
return unsolvable
```

Breadth-first search with duplicate detection
Random walk

\[
\sigma := \text{make-root-node}(\text{init})
\]

\[
\textbf{forever:}
\]

\[
\text{if } \text{is-goal}(\text{state}(\sigma)):
\]

\[
\text{return extract-solution}(\sigma)
\]

Choose a random element \( \langle o, s \rangle \) from \( \text{succ}(\text{state}(\sigma)) \).

\[
\sigma := \text{make-node}(\sigma, o, s)
\]

- The algorithm usually does not find any solutions, unless almost every sequence of actions is a plan.
- Often, it runs indefinitely without making progress.
- It can also fail by reaching a dead end, a state with no successors. This is a weakness of many local search approaches.

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Heuristic search algorithms: systematic

- Heuristic search algorithms are the most common and overall most successful algorithms for classical planning.

Popular systematic heuristic search algorithms:

- greedy best-first search
- A* 
- weighted A*
- IDA*
- depth-first branch-and-bound search
- ...
**Heuristic search: idea**

- **Uninformed search**
- **Heuristic search**
- **Heuristics**
- **Systematic search**
- **Local search**
- **Summary**

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**Required ingredients for heuristic search**

A **heuristic search algorithm** requires one more operation in addition to the definition of a search space.

**Definition (heuristic function)**

Let $\Sigma$ be the set of nodes of a given search space. A **heuristic function** or **heuristic** (for that search space) is a function $h : \Sigma \rightarrow \mathbb{N}_0 \cup \{\infty\}$.

The value $h(\sigma)$ is called the **heuristic estimate** or heuristic **value** of heuristic $h$ for node $\sigma$. It is supposed to estimate the distance from $\sigma$ to the nearest goal node.

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**Heuristics applied to nodes or states?**

- Most texts apply heuristic functions to states, not nodes.
- This is slightly less general than our definition:
  - Given a state heuristic $h$, we can define an equivalent node heuristic as $h'(\sigma) := h(\text{state}(\sigma))$.
  - The opposite is not possible. (Why not?)
- There is good justification for only allowing state-defined heuristics: why should the estimated distance to the goal depend on how we ended up in a given state $s$?
- We call heuristics which don't just depend on $\text{state}(\sigma)$ **pseudo-heuristics**.
- In practice there are sometimes good reasons to have the heuristic value depend on the generating path of $\sigma$ (e.g., **landmark pseudo-heuristic**, Richter et al. 2008).
Let $\Sigma$ be the set of nodes of a given search space.

**Definition (optimal/perfect heuristic)**

The optimal or perfect heuristic of a search space is the heuristic $h^*$ which maps each search node $\sigma$ to the length of a shortest path from $\text{state}(\sigma)$ to any goal state.

Note: $h^*(\sigma) = \infty$ iff no goal state is reachable from $\sigma$.

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**Properties of heuristics**

A heuristic $h$ is called
- **safe** if $h^*(\sigma) = \infty$ for all $\sigma \in \Sigma$ with $h(\sigma) = \infty$
- **goal-aware** if $h(\sigma) = 0$ for all goal nodes $\sigma \in \Sigma$
- **admissible** if $h(\sigma) \leq h^*(\sigma)$ for all nodes $\sigma \in \Sigma$
- **consistent** if $h(\sigma) \leq h(\sigma') + 1$ for all nodes $\sigma, \sigma' \in \Sigma$ such that $\sigma'$ is a successor of $\sigma$.

Relationships?

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**Greedy best-first search**

Greedy best-first search (with duplicate detection)

$open := \text{new min-heap ordered by } (\sigma \mapsto h(\sigma))$

$open.\text{insert}(\text{make-root-node}(\text{init}()))$

$closed := \emptyset$

while not $open.\text{empty}()$:  

\[
\sigma = \text{open.\text{pop-min}()}
\]

if $\text{state}(\sigma) \notin \text{closed}$:

\[
\text{closed} := \text{closed} \cup \{\text{state}(\sigma)\}
\]

if $\text{is-goal}(\text{state}(\sigma))$:

return $\text{extract-solution}(\sigma)$

for each $\langle o, s \rangle \in \text{succ}(\text{state}(\sigma))$:  

\[
\sigma' := \text{make-node}(\sigma, o, s)
\]

if $h(\sigma') < \infty$:

\[
\text{open.\text{insert}}(\sigma')
\]

return unsolvable

---

**Properties of greedy best-first search**

- one of the three most commonly used algorithms for satisficing planning
- **complete** for safe heuristics (due to duplicate detection)
- **suboptimal** unless $h$ satisfies some very strong assumptions (similar to being perfect)
- invariant under all strictly monotonic transformations of $h$
  (e.g., scaling with a positive constant or adding a constant)
A* (with duplicate detection and reopening)

\[ \text{open} := \text{new min-heap ordered by } (\sigma \rightarrow g(\sigma) + h(\sigma)) \]

\[ \text{open} . \text{insert}(\text{make-root-node}(\text{init})) \]

\[ \text{closed} := \emptyset \]

\[ \text{distance} := \emptyset \]

while not \text{open}.empty():

\[ \sigma = \text{open} . \text{pop-min}() \]

if state(\sigma) \notin \text{closed} or g(\sigma) < \text{distance(state(\sigma))}:

\[ \text{closed} := \text{closed} \cup \{ \text{state(\sigma)} \} \]

\[ \text{distance} (\text{state}(\sigma)) := g(\sigma) \]

if is-goal(state(\sigma)):

return extract-solution(\sigma)

for each \langle \sigma', s \rangle \in \text{succ(state(\sigma))}:

\[ \sigma' := \text{make-node} (\sigma, s) \]

if \( h(\sigma') < \infty \):

\[ \text{open} . \text{insert}(\sigma') \]

return unsolvable
Introduction

Uninformed search

Heuristic search

Heuristics

Systematic search

Local search

Summary

A∗ example

Example

Terminology for A∗

- f value of a node: defined by \( f(\sigma) := g(\sigma) + h(\sigma) \)
- generated nodes: nodes inserted into open at some point
- expanded nodes: nodes \( \sigma \) popped from open for which the test against closed and distance succeeds
- reexpanded nodes: expanded nodes for which state(\( \sigma \))∈ closed upon expansion (also called reopened nodes)

Properties of A∗

- the most commonly used algorithm for optimal planning
- rarely used for satisficing planning
- complete for safe heuristics (even without duplicate detection)
- optimal if h is admissible (even without duplicate detection)
- never reopens nodes if h is consistent

Implementation notes:

- in the heap-ordering procedure, it is considered a good idea to break ties in favour of lower h values
- can simplify algorithm if we know that we only have to deal with consistent heuristics
- common, hard to spot bug: test membership in closed at the wrong time
**Weighted A***

**Weighted A*** (with duplicate detection and reopening)

\[
open := \text{new min-heap ordered by } (\sigma \mapsto g(\sigma) + W \cdot h(\sigma)) \\
open.\text{insert}(\text{make-root-node}(\text{init}())) \\
closed := \emptyset \\
distance := 0 \\
\text{while not open.}\text{empty}(): \\
\begin{align*}
\sigma &= \text{open.}\text{pop-min}() \\
&\quad \text{if state}(\sigma) \notin \text{closed} \text{ or } g(\sigma) < \text{distance(state}(\sigma)):
\quad \text{closed} := \text{closed} \cup \{\text{state}(\sigma)\} \\
\quad \text{distance}(\sigma) := g(\sigma) \\
&\quad \text{if is-goal(state}(\sigma)):
\quad \text{return extract-solution}(\sigma) \\
&\quad \text{for each } (o, s) \in \text{succ}(\text{state}(\sigma)):
\quad \sigma' := \text{make-node}(\sigma, o, s) \\
&\quad \text{if } h(\sigma') < \infty: \text{open.}\text{insert}(\sigma') \\
\end{align*}
\]

\[
\text{return unsolvable}
\]

**Properties of weighted A***

The weight \( W \in \mathbb{R}^+_0 \) is a parameter of the algorithm.

- for \( W = 0 \), behaves like breadth-first search
- for \( W = 1 \), behaves like \( A^* \)
- for \( W \to \infty \), behaves like greedy best-first search

**Properties:**

- one of the most commonly used algorithms for satisficing planning
- for \( W > 1 \), can prove similar properties to \( A^* \), replacing optimal with bounded suboptimal: generated solutions are at most a factor \( W \) as long as optimal ones

**Enforced hill-climbing**

**Enforced hill-climbing: procedure improve**

\[
\text{def improve}(\sigma_0): \\
\begin{align*}
&\quad \text{queue} := \text{new fifo-queue} \\
&\quad \text{queue}.\text{push-back}(\sigma_0) \\
&\quad \text{closed} := \emptyset \\
&\quad \text{while not queue.}\text{empty}(): \\
&\quad \quad \sigma = \text{queue.}\text{pop-front}() \\
&\quad \quad \text{if state}(\sigma) \notin \text{closed}: \\
&\quad \quad \quad \text{closed} := \text{closed} \cup \{\text{state}(\sigma)\} \\
&\quad \quad \quad \text{if } h(\sigma) < h(\sigma_0): \\
&\quad \quad \quad \quad \text{return } \sigma \\
&\quad \quad \quad \text{for each } (o, s) \in \text{succ}(\text{state}(\sigma)): \\
&\quad \quad \quad \quad \sigma' := \text{make-node}(\sigma, o, s) \\
&\quad \quad \quad \quad \text{queue.}\text{push-back}(\sigma') \\
&\quad \quad \text{fail} \\
\end{align*}
\]

\[ \Rightarrow \text{breadth-first search for more promising node than } \sigma_0 \]
Enforced hill-climbing (ctd.)

Enforced hill-climbing
\[
\sigma := \text{make-root-node}(\text{init}())
\]
\[\text{while not is-goal(state(\sigma))}:
\]
\[\sigma := \text{improve}(\sigma)
\]
\[\text{return extract-solution(\sigma)}
\]

- one of the three most commonly used algorithms for satisficing planning
- can fail if procedure improve fails (when the goal is unreachable from \(\sigma_0\))
- complete for undirected search spaces (where the successor relation is symmetric) if \(h(\sigma) = 0\) for all goal nodes and only for goal nodes

Summary (ctd.)

- **heuristics:** estimators for “distance to goal node”
  - usually: the more accurate, the better performance
  - desiderata: safe, goal-aware, admissible, consistent
  - the ideal: perfect heuristic \(h^*\)
- most common algorithms for satisficing planning:
  - greedy best-first search
  - weighted A^*
  - enforced hill-climbing
- most common algorithm for optimal planning:
  - A^*