

Principles of AI Planning

1. Introduction

Albert-Ludwigs-Universität Freiburg



**UNI
FREIBURG**

Bernhard Nebel and Robert Mattmüller

October 22nd, 2014

1 About the course



- Coordinates
- Rules

About...

Coordinates

Rules

Introduction

Lecturers

Prof. Dr. Bernhard Nebel

- **email:** `nebel@informatik.uni-freiburg.de`
- **office:** room 052-00-029
- **consultation:** Tuesday, 12:15-13:00

Dr. Robert Mattmüller

- **email:** `mattmuel@informatik.uni-freiburg.de`
- **office:** room 052-00-045
- **consultation:** by appointment (email) or just drop by in the office

[About...](#)

[Coordinates](#)

[Rules](#)

[Introduction](#)

[About...](#)

[Coordinates](#)

[Rules](#)

[Introduction](#)

Exercises

Robert Mattmüller

David Speck

- **email:** `david.speck@pluto.uni-freiburg.de`
- **consultation:** by appointment (email)

Lectures

- **time:** Wednesday 14:15-16:00, Friday 14:15-15:00
- **place:** SR 101-00-010/14

Exercises

- **time:** Friday 15:15-16:00
- **place:** SR 101-00-010/14

Course web site

<http://gki.informatik.uni-freiburg.de/teaching/ws1415/aip/>

- [main page](#): course description
- [lecture page](#): slides
- [exercise page](#): assignments, software
- [bibliography page](#): literature references and papers

- no script, no recommended textbook (although two textbooks exist, but they are not necessary for this course)
 - Geffner and Bonet (2013), A Concise Introduction to Models and Methods for Automated Planning
(comes closest to this course, includes relatively recent research results)
 - Nau, Ghallab, and Traverso (2004), Automated Planning: Theory and Practice
(very different from this course, a bit outdated)
- slides handed out during lectures and available on the web
- additional resources: bibliography page on web +
ask us!

About ...

Coordinates

Rules

Introduction

Acknowledgments:

- slides based on earlier courses by Jussi Rintanen, Bernhard Nebel and Malte Helmert
- many figures by Gabi Röger

Students of Computer Science:

- Master of Science, any year
- Bachelor of Science, ~3rd year

Other students:

- advanced study period (~4th year)

Course prerequisites:

- [propositional logic](#): syntax and semantics
- [foundations of AI](#): search, heuristic search
- [computational complexity theory](#): decision problems, reductions, NP-completeness

- 6 ECTS points
- special lecture in specialization field
[Cognitive Technical Systems](#)
- [oral exam](#) of about 30 minutes for B.Sc. students
- [written or oral exam](#) for M.Sc. students
(depending on their number)

Exercises (written assignments):

- handed out once a week
- due one week later, before the lecture
- discussed in the next exercise session
- may be solved in groups of two students ($2 \neq 3$)
- successful participation prerequisite for exam admission

- points can be earned for “reasonable” solutions to exercises.
- at least 50% of points prerequisite for admission to final exam.

What is plagiarism?

- passing off solutions as your own that are not based on your ideas (work of other students, Internet, books, ...)
- <http://en.wikipedia.org/wiki/Plagiarism> is a good intro

Consequence: no admission to the final exam.

- We may (!) be generous on first offense.
- Don't tell us "We did the work together."
- Don't tell us "I did not know this was not allowed."

About ...

Coordinates

Rules

Introduction

- What is planning?
- Problem classes
- Dynamics
- Observability
- Objectives
- Planning vs. game theory
- Summary

About...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game
theory

Summary

Planning

“Planning is the art and practice of thinking before acting.”

— Patrik Haslum

- intelligent decision making: What actions to take?
- general-purpose problem representation
- algorithms for solving any problem expressible in the representation
- application areas:
 - high-level planning for intelligent robots
 - autonomous systems: NASA Deep Space One, ...
 - problem solving (single-agent games like Rubik's cube)

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

Why is planning difficult?



- solutions to classical planning problems are **paths from an initial state to a goal state** in the **transition graph**
 - efficiently solvable by Dijkstra's algorithm in $O(|V| \log |V| + |E|)$ time
 - Why don't we solve all planning problems this way?
- state spaces may be **huge**: $10^{10}, 10^{100}, 10^{1000}, \dots$ states
 - constructing the transition graph is infeasible!
 - planning algorithms try to **avoid constructing whole graph**
- planning algorithms are often much more efficient than obvious solution methods constructing the transition graph and using e. g. Dijkstra's algorithm

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- **dynamics:** deterministic, nondeterministic or probabilistic
 - **observability:** full, partial or none
 - **horizon:** finite or infinite
 - ...
-
- 1 classical planning
 - 2 conditional planning with full observability
 - 3 conditional planning with partial observability
 - 4 conformant planning
 - 5 Markov decision processes (MDP)
 - 6 partially observable MDPs (POMDP)

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- **dynamics:** **deterministic**, nondeterministic or probabilistic
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 - 2 conditional planning with full observability
 - 3 conditional planning with partial observability
 - 4 conformant planning
 - 5 Markov decision processes (MDP)
 - 6 partially observable MDPs (POMDP)

[About ...](#)

[Introduction](#)

[What is planning?](#)

Problem classes

[Dynamics](#)

[Observability](#)

[Objectives](#)

[Planning vs. game theory](#)

[Summary](#)

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 - 2 **conditional planning with full observability**
 - 3 conditional planning with partial observability
 - 4 conformant planning
 - 5 Markov decision processes (MDP)
 - 6 partially observable MDPs (POMDP)

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- **dynamics:** deterministic, **nondeterministic** or probabilistic
 - **observability:** full, **partial** or none
 - **horizon:** **finite** or **infinite**
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- 1 classical planning
 - 2 conditional planning with full observability
 - 3 **conditional planning with partial observability**
 - 4 conformant planning
 - 5 Markov decision processes (MDP)
 - 6 partially observable MDPs (POMDP)

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- **dynamics:** **deterministic**, **nondeterministic** or probabilistic
 - **observability:** full, partial or **none**
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-
- 1 classical planning
 - 2 conditional planning with full observability
 - 3 conditional planning with partial observability
 - 4 **conformant planning**
 - 5 Markov decision processes (MDP)
 - 6 partially observable MDPs (POMDP)

About ...

[Introduction](#)

[What is planning?](#)

[Problem classes](#)

[Dynamics](#)

[Observability](#)

[Objectives](#)

[Planning vs. game theory](#)

[Summary](#)

- **dynamics:** deterministic, nondeterministic or **probabilistic**
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 - 2 conditional planning with full observability
 - 3 conditional planning with partial observability
 - 4 conformant planning
 - 5 **Markov decision processes (MDP)**
 - 6 partially observable MDPs (POMDP)

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- **dynamics**: deterministic, nondeterministic or **probabilistic**
 - **observability**: full, **partial** or none
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-
- 1 classical planning
 - 2 conditional planning with full observability
 - 3 conditional planning with partial observability
 - 4 conformant planning
 - 5 Markov decision processes (MDP)
 - 6 **partially observable MDPs (POMDP)**

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

Deterministic dynamics

Action + current state **uniquely** determine successor state.

Nondeterministic dynamics

For each action and current state there may be **several possible** successor states.

Probabilistic dynamics

For each action and current state there is a **probability distribution** over possible successor states.

Analogy: deterministic versus nondeterministic automata

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

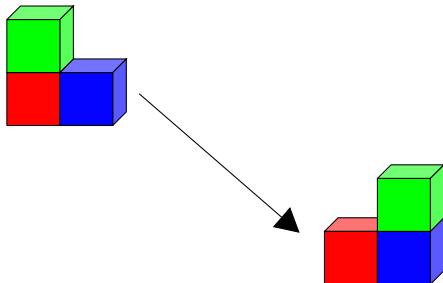
Objectives

Planning vs. game theory

Summary

Deterministic dynamics example

Moving objects with a robotic hand:
move the green block onto the blue block.



About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

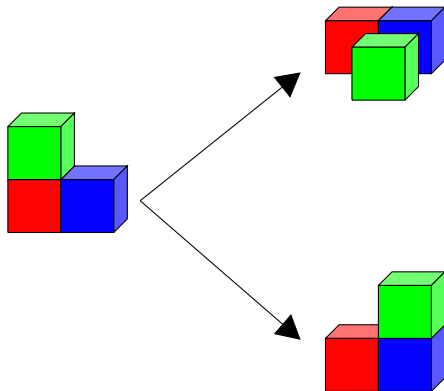
Objectives

Planning vs. game
theory

Summary

Nondeterministic dynamics example

Moving objects with an **unreliable** robotic hand:
move the green block onto the blue block.



About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

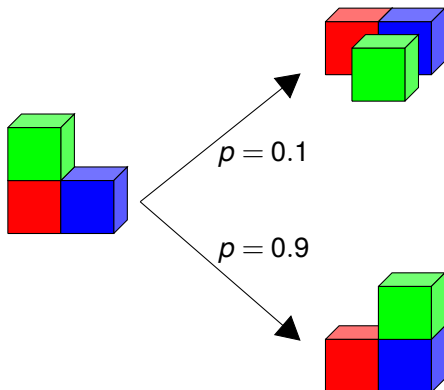
Objectives

Planning vs. game
theory

Summary

Probabilistic dynamics example

Moving objects with an **unreliable** robotic hand:
move the green block onto the blue block.



About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

Full observability

Observations determine current world state **uniquely**.

Partial observability

Observations determine current world state **only partially**: we only know that current state is one of several possible ones.

No observability

There are **no observations** to narrow down possible current states. However, can use knowledge of **action dynamics** to deduce which states we might be in.

Consequence: If observability is not full, must represent the **knowledge** an agent has.

About...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

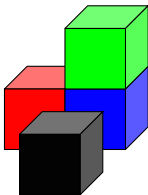
Planning vs. game theory

Summary

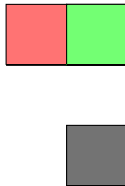
What difference does observability make?



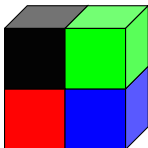
Camera A



Camera B



Goal



About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

- 1 Reach a goal state.
 - **Example:** Earn 500 Euro.
- 2 Stay in goal states indefinitely (infinite horizon).
 - **Example:** Never allow bank account balance to be negative.
- 3 Maximize the probability of reaching a goal state.
 - **Example:** To be able to finance buying a house by 2024 study hard and save money.
- 4 Collect the maximal **expected** rewards/minimal expected costs (infinite horizon).
 - **Example:** Maximize your future income.
- 5 ...

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary



- Game theory addresses decision making in multi-agent setting: “Assuming that the other agents are rational, what do I have to do to achieve my goals?”
- Game theory is related to **multi-agent planning**.
- In this course we concentrate on **single-agent planning**.
- Some of the techniques are also applicable to special cases of multi-agent planning.
 - **Example:** Finding a **winning strategy** of a game like chess. In this case it is not necessary to distinguish between **an intelligent opponent** and **a randomly behaving opponent**.
- Game theory in general is about **optimal strategies** which do not necessarily guarantee winning. For example card games like poker do not have a winning strategy.

About ...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary

What do you learn in this course?

- emphasis on **classical** planning (“simplest” case)
- brief digression to **nondeterministic** planning
- **theoretical background** for planning
 - formal **problem definition**
 - basic **theoretical notions**
(e. g., normal forms, progression, regression)
 - **computational complexity** of planning
- **algorithms** for planning:
 - based on **heuristic search**

Many of these techniques are applicable to problems outside AI as well.

- **hands-on experience** with a classical planner (probably)

About...

Introduction

What is planning?

Problem classes

Dynamics

Observability

Objectives

Planning vs. game theory

Summary