

Principles of AI Planning

4. PDDL

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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 operator $\text{drive_car_from_to}(x, y_1, y_2)$:

$$x \in \{\text{car1}, \text{car2}\},$$

$$y_1 \in \{\text{Freiburg}, \text{Strasbourg}\},$$

$$y_2 \in \{\text{Freiburg}, \text{Strasbourg}\}$$

$$\langle \text{in}(x, y_1), \text{in}(x, y_2) \wedge \neg \text{in}(x, y_1) \rangle$$

corresponds to the operators

$$\langle \text{in}(\text{car1}, \text{Freiburg}), \text{in}(\text{car1}, \text{Strasbourg}) \wedge \neg \text{in}(\text{car1}, \text{Freiburg}) \rangle,$$

$$\langle \text{in}(\text{car1}, \text{Strasbourg}), \text{in}(\text{car1}, \text{Freiburg}) \wedge \neg \text{in}(\text{car1}, \text{Strasbourg}) \rangle,$$

$$\langle \text{in}(\text{car2}, \text{Freiburg}), \text{in}(\text{car2}, \text{Strasbourg}) \wedge \neg \text{in}(\text{car2}, \text{Freiburg}) \rangle,$$

$$\langle \text{in}(\text{car2}, \text{Strasbourg}), \text{in}(\text{car2}, \text{Freiburg}) \wedge \neg \text{in}(\text{car2}, \text{Strasbourg}) \rangle,$$

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

$$\langle \text{in}(\text{car1}, \text{Freiburg}), \text{in}(\text{car1}, \text{Freiburg}) \wedge \neg \text{in}(\text{car1}, \text{Freiburg}) \rangle.$$

Existential quantification (for formulae only)

Finite disjunctions $\varphi(a_1) \vee \dots \vee \varphi(a_n)$ represented as
 $\exists x \in \{a_1, \dots, a_n\} : \varphi(x)$.

Universal quantification (for formulae and effects)

Finite conjunctions $\varphi(a_1) \wedge \dots \wedge \varphi(a_n)$ represented as
 $\forall x \in \{a_1, \dots, a_n\} : \varphi(x)$.

Example

$\exists x \in \{A, B, C\} : in(x, Freiburg)$ is a short-hand for
 $in(A, Freiburg) \vee in(B, Freiburg) \vee in(C, Freiburg)$.

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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

```
(and (or (on A B) (on A C))  
      (or (on B A) (on B C))  
      (or (on C A) (on A B)))
```

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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)
               )
)
```



- (: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>)
```

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■ 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)))
)
```

Example

The Fast Downward Planner



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

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The Fast Downward Planner



Fast Downward is available at

<http://www.fast-downward.org/>

Installation:

Follow instructions at

[http://www.fast-downward.org/
ObtainingAndRunningFastDownward](http://www.fast-downward.org/ObtainingAndRunningFastDownward)

Running:

Follow instructions at

<http://www.fast-downward.org/PlannerUsage>

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Example run of Fast Downward



```
# ./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
```

[...]

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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)))
)
```