

Informed Search

Oren Etzioni

CSE 473

University of Washington

Best-first Search

Generalization of breadth first search

Priority queue of nodes to be explored

Cost function $f(n)$ applied to each node

Add initial state to priority queue

While queue not empty

Node = head(queue)

If goal?(node) then return node

Add children of node to queue

Old Friends

- Breadth first = best first
With $f(n) = \text{depth}(n)$
- Dijkstra's Algorithm = best first
With $f(n) = g(n)$
Where $g(n) = \text{sum of edge costs from start to } n$
Space bound (stores all generated nodes)

A* Search

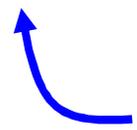
- Hart, Nilsson & Rafael 1968

Best first search with $f(n) = g(n) + h(n)$

Where $g(n)$ = sum of edge costs from start to n

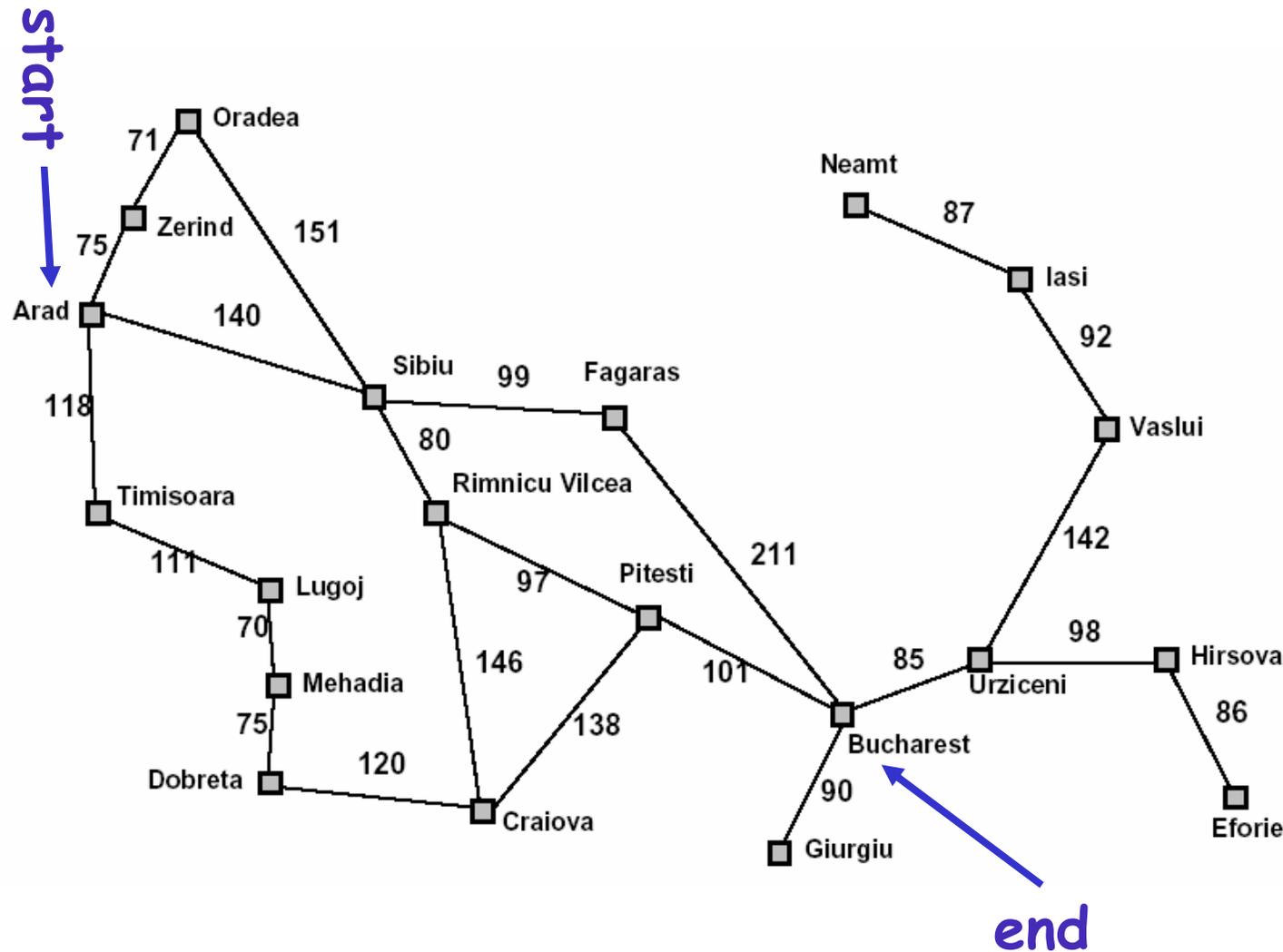
And $h(n)$ = estimate of lowest cost path $n \rightarrow$ goal

If $h(n)$ is **admissible** then search will find optimal

 Underestimates cost
of any solution which
can be reached from node

Space bound since must maintain queue

European Example

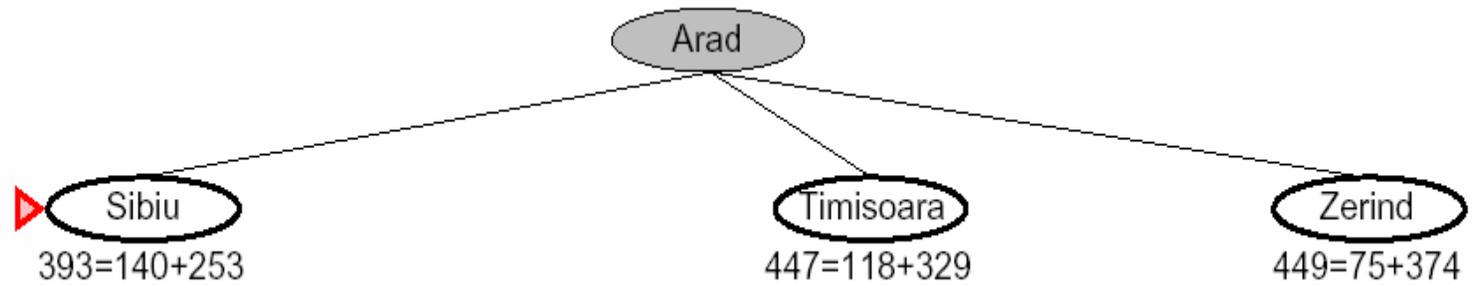


Straight-line distance to Bucharest	
Arad	366
Bucharest	0
Craiova	160
Dobreta	242
Eforie	161
Fagaras	178
Giurgiu	77
Hirsova	151
Iasi	226
Lugoj	244
Mehadia	241
Neamt	234
Oradea	380
Pitesti	98
Rimnicu Vilcea	193
Sibiu	253
Timisoara	329
Urziceni	80
Vaslui	199
Zerind	374

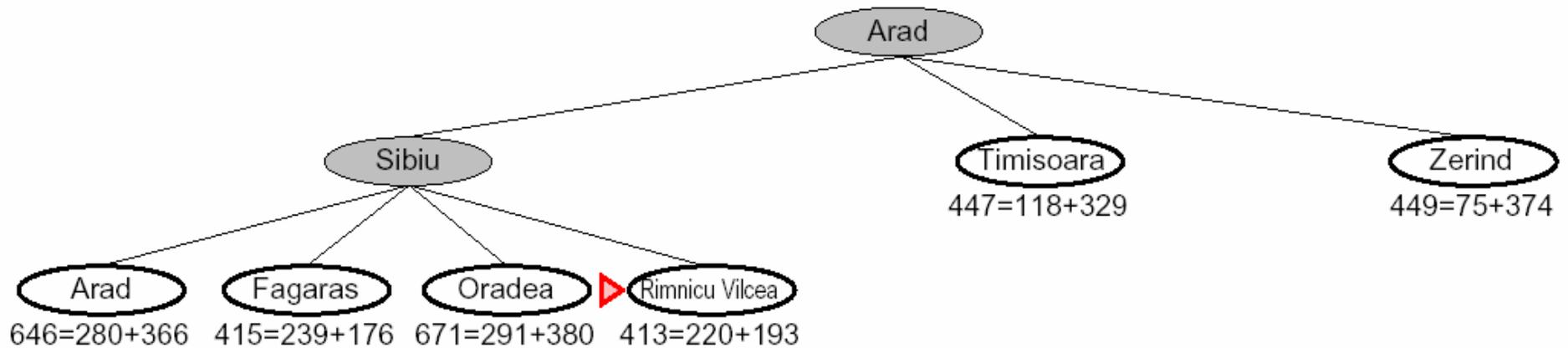
A* Example

▶ Arad
366=0+366

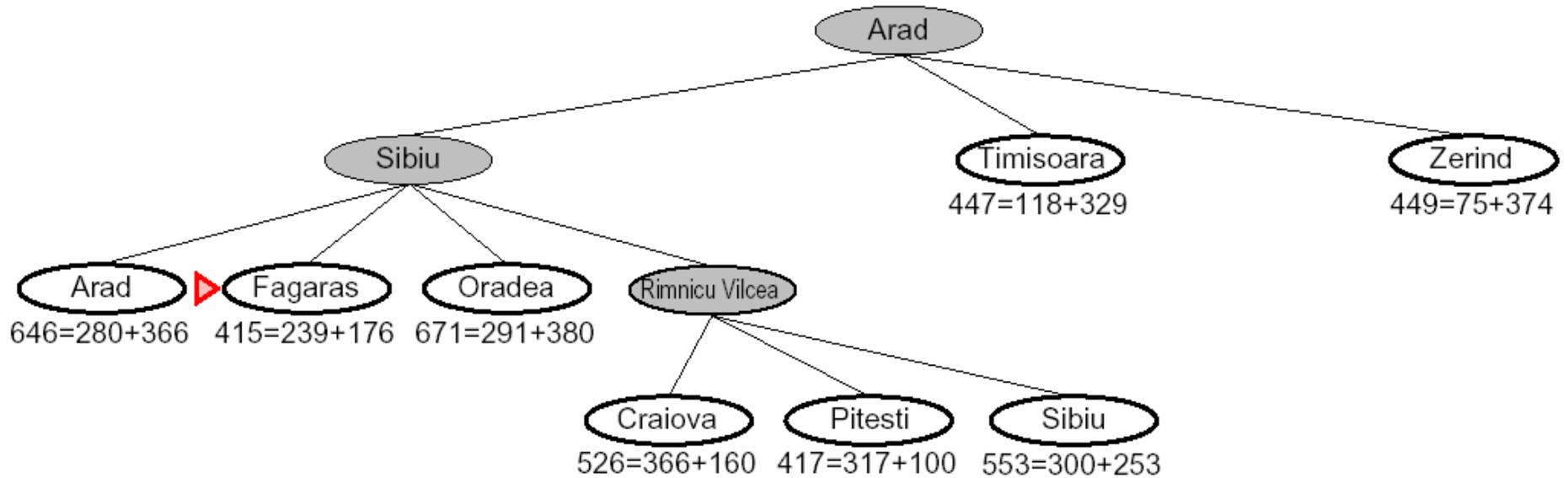
A* Example



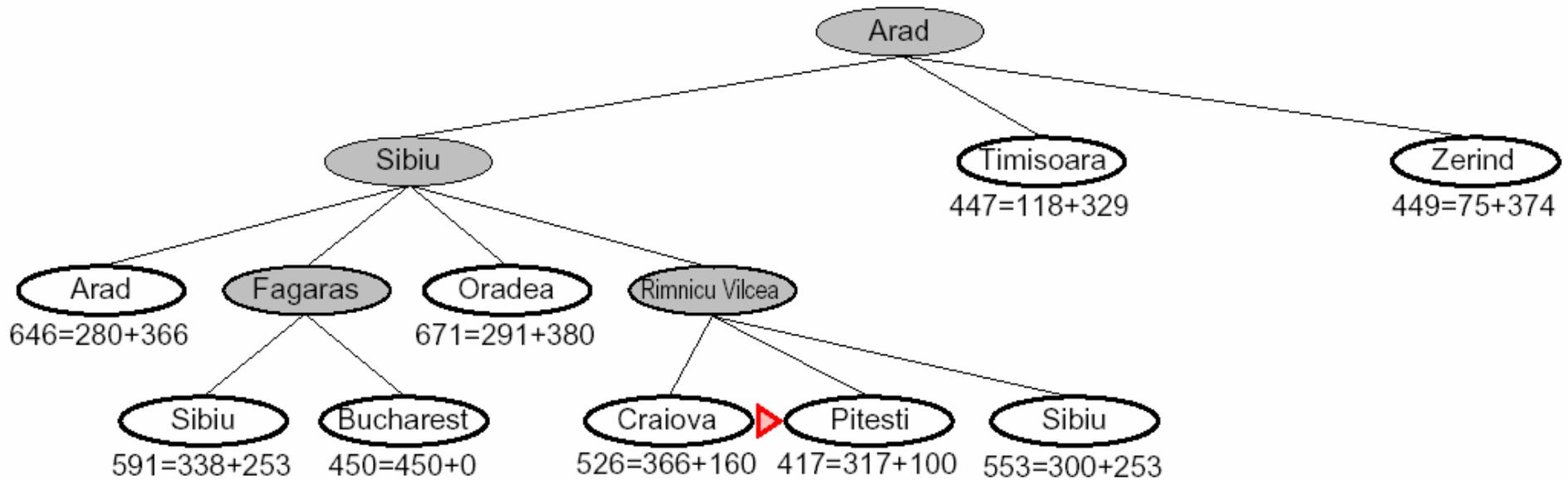
A* Example



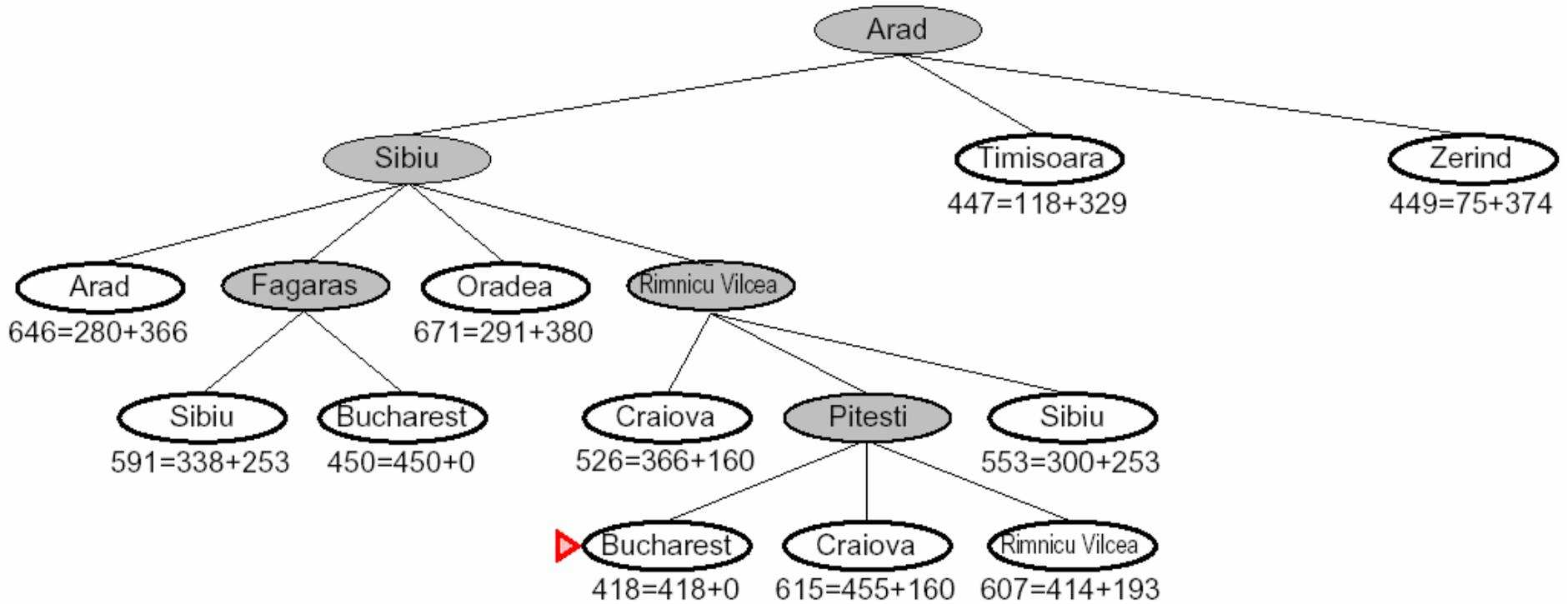
A* Example



A* Example

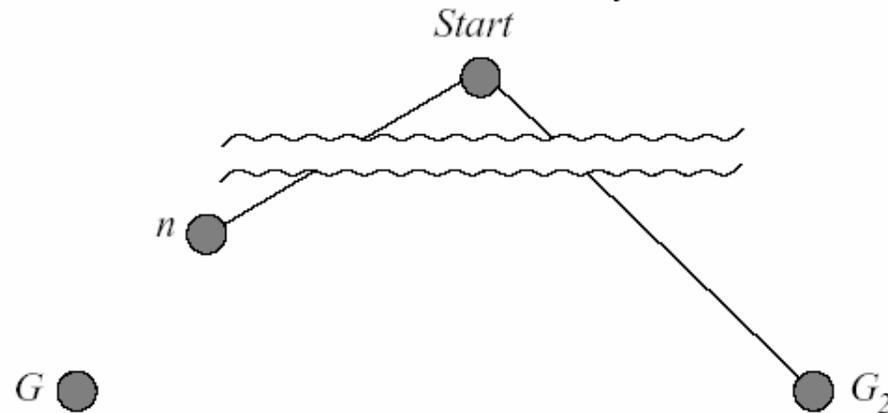


A* Example



Optimality of A*

Suppose some suboptimal goal G_2 has been generated and is in the queue. Let n be an unexpanded node on a shortest path to an optimal goal G_1 .



$$\begin{aligned} f(G_2) &= g(G_2) && \text{since } h(G_2) = 0 \\ &> g(G_1) && \text{since } G_2 \text{ is suboptimal} \\ &\geq f(n) && \text{since } h \text{ is admissible} \end{aligned}$$

Since $f(G_2) > f(n)$, A* will never select G_2 for expansion

A* Summary

- Pros
- Cons

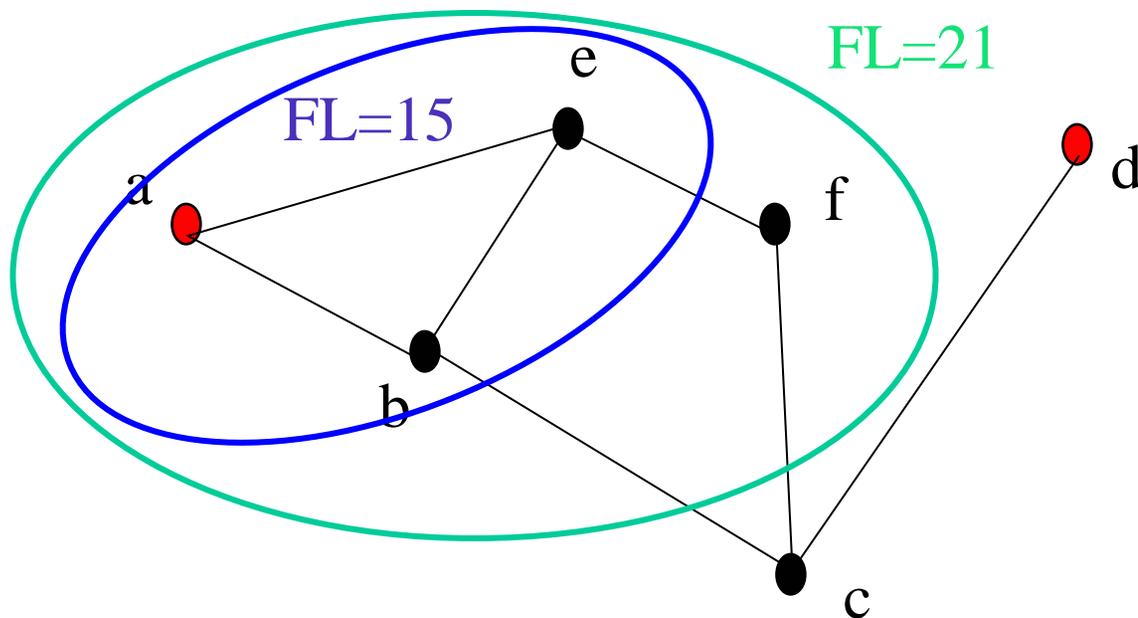
Iterative-Deepening A*

- Like iterative-deepening depth-first, but...
- Depth bound modified to be an **f-limit**

Start with $\text{limit} = h(\text{start})$

Prune any node if $f(\text{node}) > \text{f-limit}$

Next $\text{f-limit} = \text{min-cost of any node pruned}$



Depth-First Branch & Bound

- Single DF search
 - uses linear space
- Keep track of best solution so far
- If $f(n) = g(n) + h(n) \geq \text{cost}(\text{best-soln})$
Then prune n
- Requires
 - Finite search tree, or
 - Good upper bound on solution cost

Beam Search

- Idea

Best first but only keep N best items on priority queue

- Evaluation

Complete?

Time Complexity?

Space Complexity?

Hill Climbing

“Gradient ascent”

- Idea

Always choose best child; no backtracking

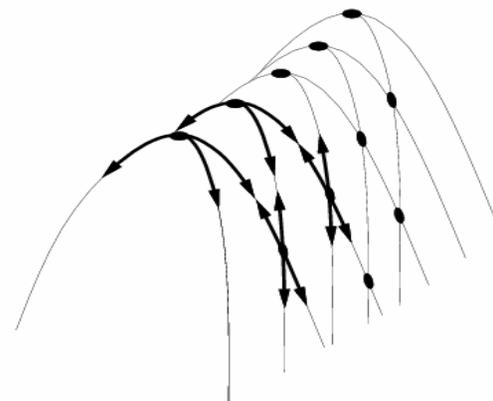
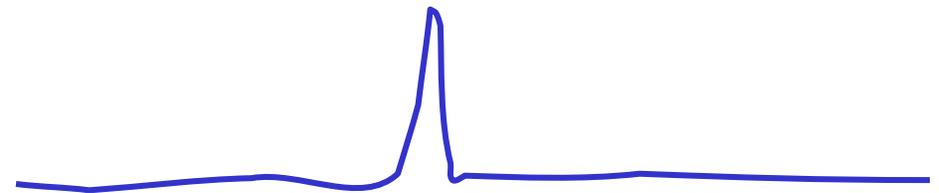
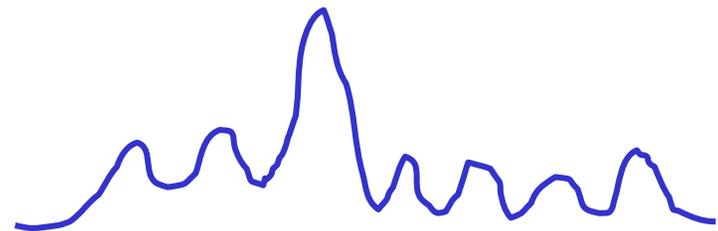
Beam search with $|queue| = 1$

- Problems?

Local maxima

Plateaus

Diagonal ridges



Randomizing Hill Climbing

- Randomly disobeying heuristic
- Random restarts
- [Add something on heavy tailed distribution]

Simulated Annealing

- Objective: avoid local minima

- Technique:

For the most part use hill climbing

When no improvement possible

- Choose random neighbor
- Let Δ be the decrease in quality
- Move to neighbor with probability $e^{-\Delta/T}$

Reduce "temperature" (T) over time

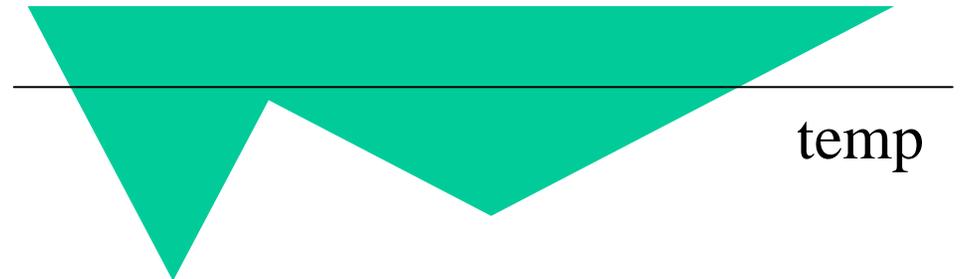
- Pros & cons

Optimal?

If T decreased slowly enough, *will* reach optimal state

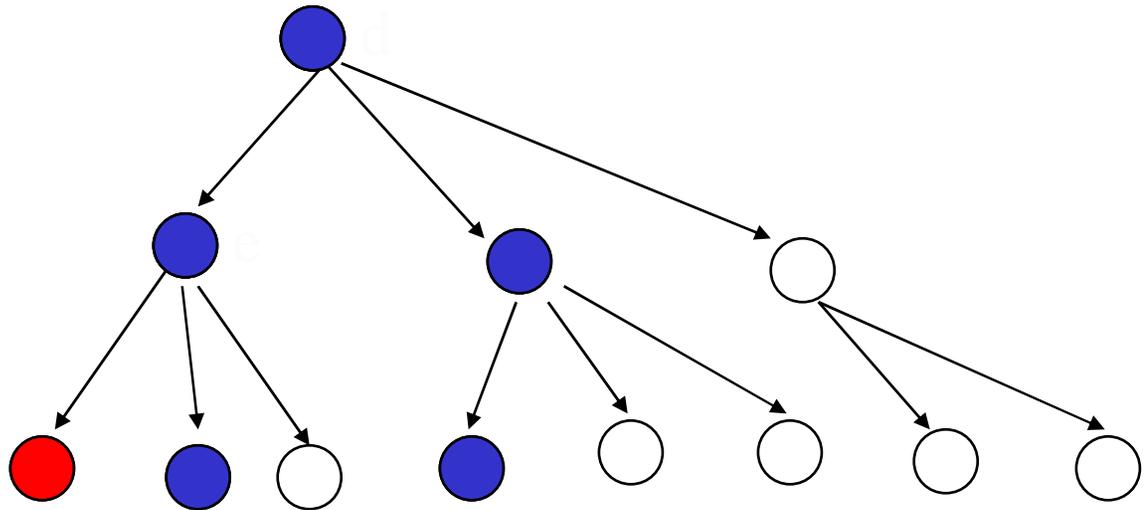
- Widely used

- See also
WalkSAT



Limited Discrepancy Search

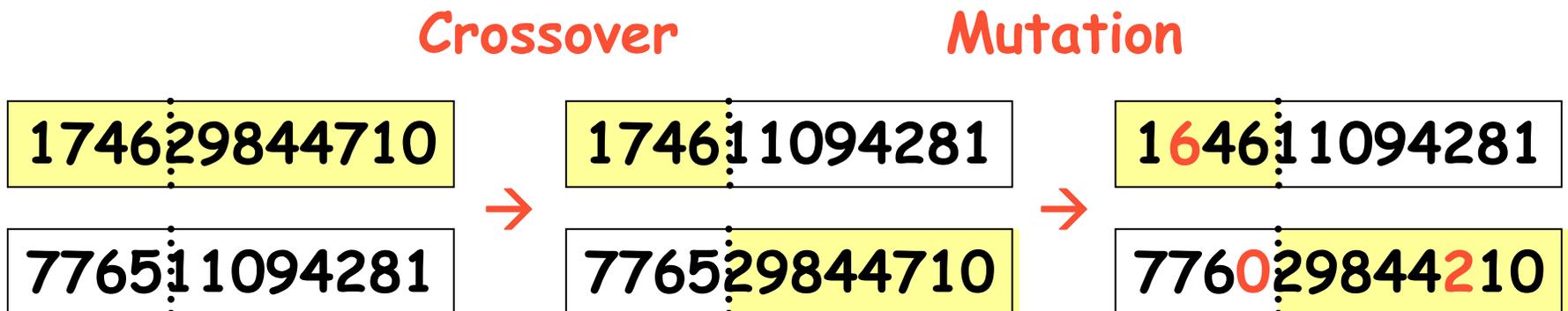
- Discrepancy bound indicates how often to violate heuristic
- Iteratively increase...



Assume that heuristic says go *left*

Genetic Algorithms

- Start with random population
 - Representation serialized
 - States are ranked with "fitness function"
- Produce new generation
 - Select random pair(s):
 - probability \sim fitness
 - Randomly choose "crossover point"
 - Offspring mix halves
 - Randomly mutate bits



Properties

- Importance of careful representation