CSE 473: Artificial Intelligence
Autumn2016

Problem Spaces & Search

Dan Weld

With slides from
Dan Klein, Stuart Russell, Andrew Moore, Luke Zettlemoyer

Logistics

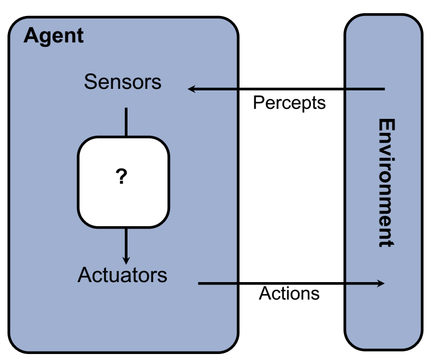
- Read Ch 3
- Do PS0 by Monday (should be easy)
- Start PS1 (harder!)

Outline

- Search Problems
- Uninformed Search Methods
  - Depth-First Search
  - Breadth-First Search
  - Uniform-Cost Search
- Heuristic Search Methods
  - Best First / Greedy Search

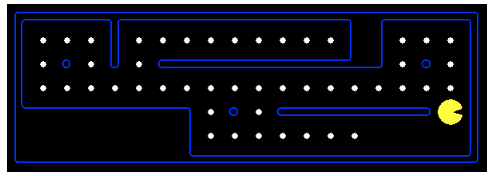
Agent *vs.* Environment

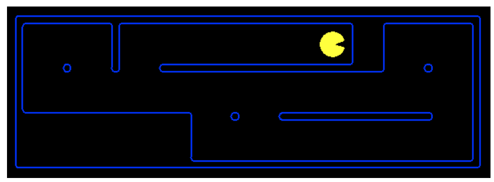
- An **agent** is an entity that *perceives* and *acts*.
- A **rational agent** selects actions that maximize its **utility function**.
- Characteristics of the **percepts, environment,** and **action space** dictate techniques for selecting rational actions.



Goal Based Agents

- Plan ahead
- Ask "what if"
- Decisions based on (hypothesized) consequences of actions
- Must have a model of how the world evolves in response to actions
- Act on how the world WOULD BE





Types of Environments

- **Fully observable** *vs.* partially observable
- **Single agent** *vs.* multiagent
- **Deterministic** *vs.* stochastic
- **Episodic** *vs.* sequential
- **Discrete** *vs.* continuous

Search thru a Problem Space (aka State Space)

- Input:
  - Set of states
  - Operators ~~*[and costs]*~~
  - Start state
  - Goal state *[or test]*

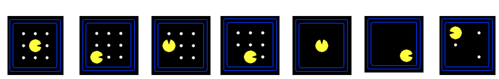
Functions: States → States

Aka "Successor Function"

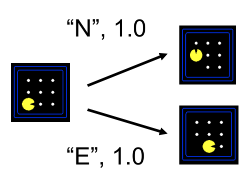
- Output:
  - Path: start ⇒ a state satisfying goal test
    [May require shortest path]
    [Sometimes just need a state that passes test]

Example: Simplified Pac-Man

- Input:
  - A state space



  - Successor function

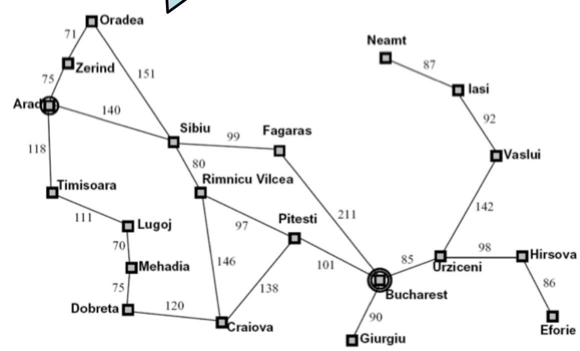


  - A start state
  - A goal test
- Output:

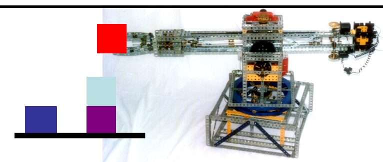
Ex: Route Planning: Arad → Bucharest

- Input:
  - Set of states
  - Operators [and costs]
  - Start state
  - Goal state (test)
- Output:

Different operators may be applicable in different states



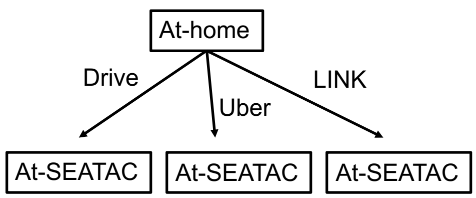
Ex: Blocks World



- Input:
  - Set of states
    Partially specified plans
  - Operators [and costs]
    Plan modification operators
  - Start state
    The null plan (no actions)
  - Goal state (test)
    A plan which provably achieves
    The desired world configuration
- Output:

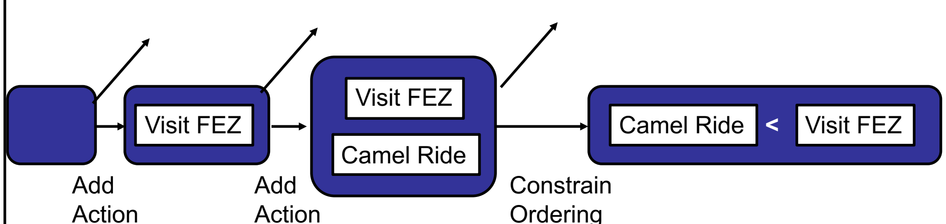
Plan Space

- Need less abstract / better motivated example



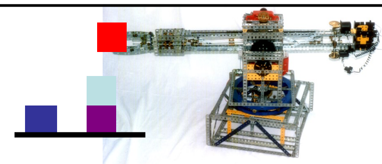
16

Plan Space



17

Multiple Problem Spaces



Real World

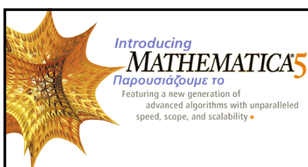
States of the world (e.g. block configurations)

Actions (take one world-state to another)

Robot's Head

- Problem Space 1
- PS states =
  - models of world states
- Operators =
  - models of actions

- Problem Space 2
- PS states =
  - partially spec. plan
- Operators =
  - plan modificat'n ops



Algebraic Simplification

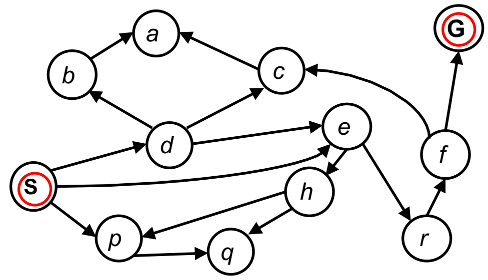
$$
\begin{aligned}
\partial_r^2 u &= -\left[E' - \frac{l(l+1)}{r^2} - r^2\right] u(r) \\
e^{-2s}\left(\partial_s^2 - \partial_s\right) u(s) &= -\left[E' - l(l+1)e^{-2s} - e^{2s}\right] u(s) \\
e^{-2s}\left[e^{\frac{1}{2}s}\left(e^{-\frac{1}{2}s}u(s)\right)'' - \frac{1}{4}u\right] &= -\left[E' - l(l+1)e^{-2s} - e^{2s}\right] u(s) \\
e^{-2s}\left[e^{\frac{1}{2}s}\left(e^{-\frac{1}{2}s}u(s)\right)''\right] &= -\left[E' - \left(l+\frac{1}{2}\right)^2 e^{-2s} - e^{2s}\right] u(s) \\
v'' &= -e^{2s}\left[E' - \left(l+\frac{1}{2}\right)^2 e^{-2s} - e^{2s}\right] v
\end{aligned}
$$

- Input:
  - Set of states
  - Operators [and costs]
  - Start state
  - Goal state (test)
- Output:

19

State Space Graphs

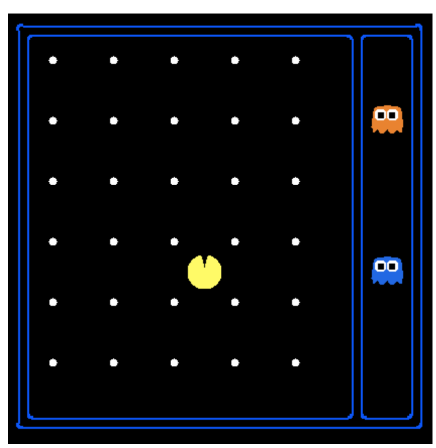
- State space graph:
  - Each node is a state
  - The operators are represented by arcs
  - Edges may be labeled with costs
- We can rarely build this graph in memory (so we don't)



Ridiculously tiny search graph for a tiny search problem

State Space Sizes?

- Search Problem: Eat all of the food
- Pacman positions: 10 x 12 = 120
- Pacman facing: up, down, left, right
- Food configurations: 2^{30}
- Ghost1 positions: 12
- Ghost 2 positions: 11

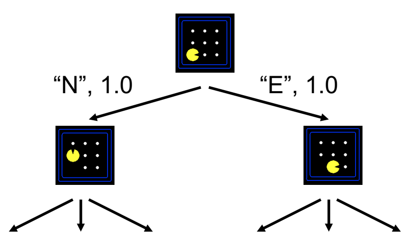


$120 \times 4 \times 2^{30} \times 12 \times 11 = 6.8 \times 10^{13}$

Search Methods

- Blind Search
  - Depth first search
  - Breadth first search
  - Iterative deepening search
  - Uniform cost search
- Local Search
- Informed Search
- Constraint Satisfaction
- Adversary Search

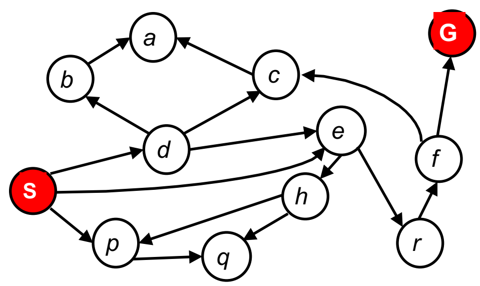
Search Trees



- A search tree:
  - Start state at the root node
  - Children correspond to successors
  - Nodes ***contain*** states, correspond to PLANS to those states
  - Edges are labeled with actions and costs
  - For most problems, we can never actually build the whole tree

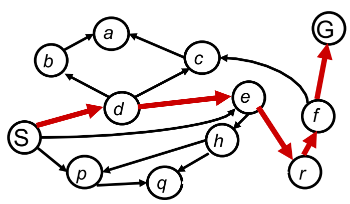
Example: Tree Search

State graph:



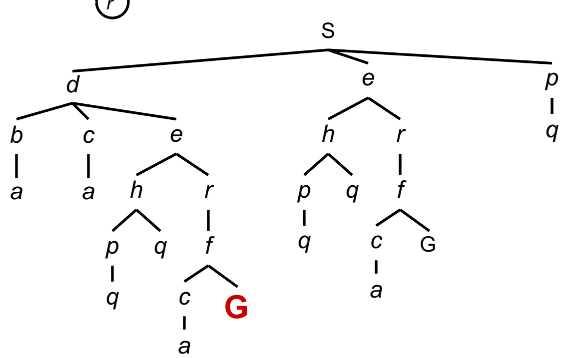
What is the search tree?

State Graphs vs. Search Trees



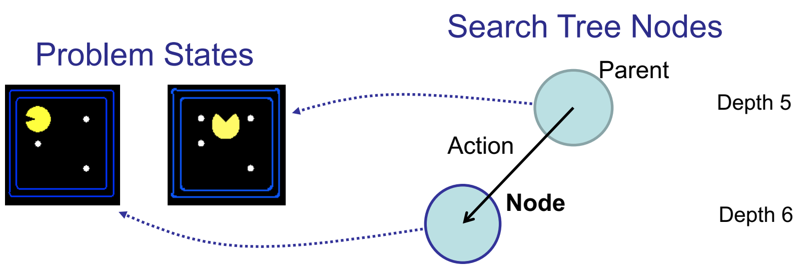
Each NODE in in the search tree denotes an entire PATH in the problem graph.

We construct both on demand – and we construct as little as possible.



States vs. Nodes

- Vertices in state space graphs are problem states
  - Represent an abstracted state of the world
  - Have successors, can be goal / non-goal, have multiple predecessors
- Vertices in search trees ("Nodes") are plans
  - Contain a problem state and one parent, a path length, a depth & a cost
  - Represent a plan (sequence of actions) which results in the node's state
  - The same problem state may be achieved by multiple search tree nodes



Building Search Trees

- Search:
  - Expand out possible nodes (plans) in the tree
  - Maintain a fringe of unexpanded nodes
  - Try to expand as few nodes as possible

General Tree Search

```
function TREE-SEARCH( problem, strategy) returns a solution, or failure
   initialize the search tree using the initial state of problem
   loop do
      if there are no candidates for expansion then return failure
      choose a leaf node for expansion according to strategy
      if the node contains a goal state then return the corresponding solution
      else expand the node and add the resulting nodes to the search tree
   end
```

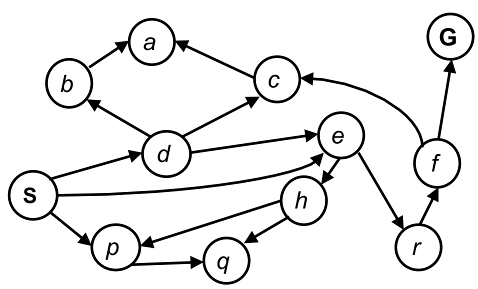
Detailed pseudocode is in the book!

Important ideas:

- Fringe (leaves of tree)
- Expansion (adding successors of a leaf)
- Exploration strategy

which fringe node to expand next?

Review: Depth First Search



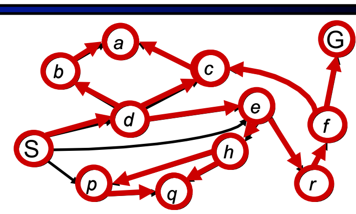
***Strategy**: expand **deepest** node first*

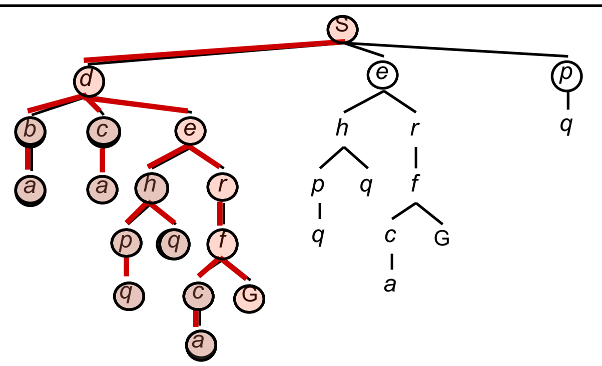
***Implementation**: Fringe is a stack - LIFO*

Review: Depth First Search

Expansion ordering:

(d,b,a,c,a,e,h,p,q,q,r,f,c,a,G)

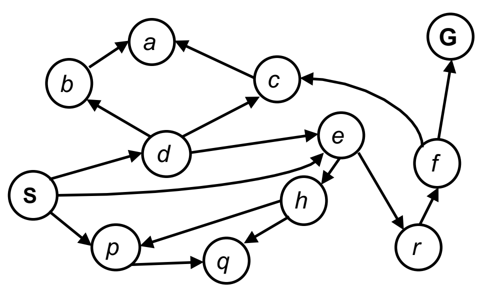




Review: Breadth First Search

***Strategy**: expand* ***shallowest** node first*

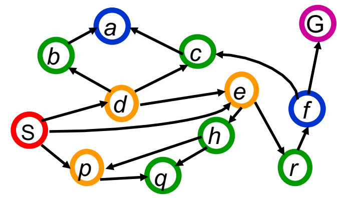
***Implementation**:*
Fringe is a queue - FIFO

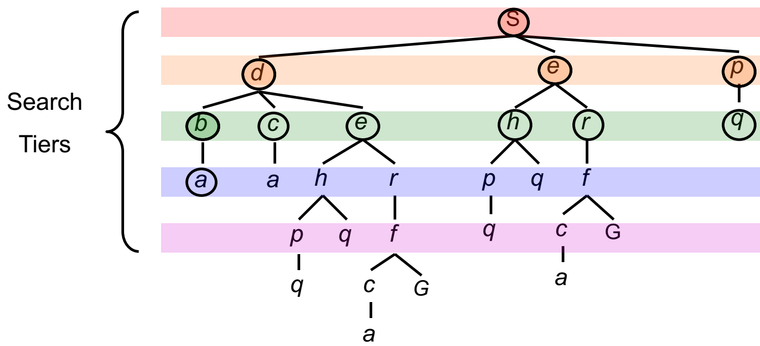


Review: Breadth First Search

Expansion order:

(S,d,e,p,b,c,e,h,r,q,a,a ,h,r,p,q,f,p,q,f,q,c,G)





Search Algorithm Properties

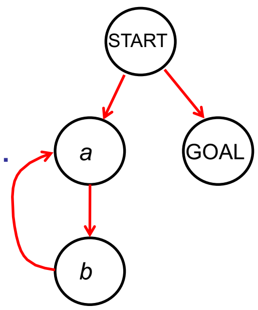
- Complete? Guaranteed to find a solution if one exists?
- Optimal? Guaranteed to find the least cost path?
- Time complexity?
- Space complexity?

Variables:

n	Number of states in the problem
b	The maximum branching factor *B* (the maximum number of successors for a state)
C^*	Cost of least cost solution
d	Depth of the shallowest solution
m	Max depth of the search tree

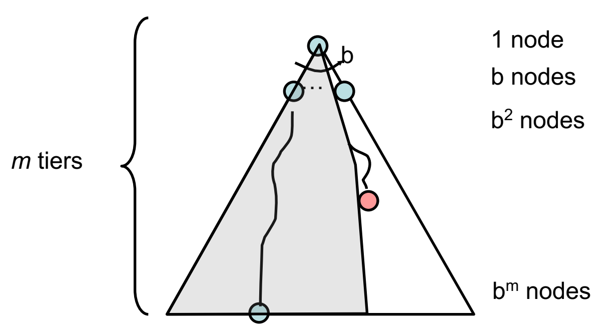
DFS

Algorithm		Complete	Optimal	Time	Space
DFS	Depth First Search	No	No	Infinite	Infinite



- Infinite paths make DFS incomplete…
  - How can we fix this?
  - Check new nodes against path from S
- Infinite search spaces still a problem

DFS

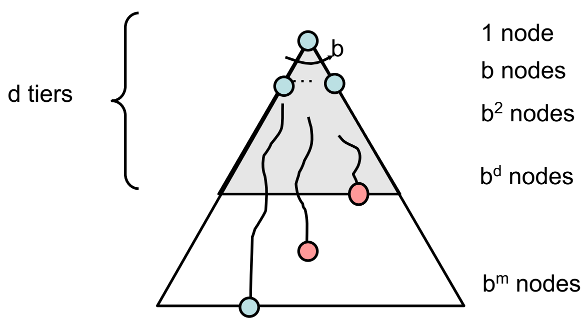


Algorithm		Complete	Optimal	Time	Space
DFS	w/ Path Checking	Y if finite	N	$O(b^m)$	$O(bm)$

* Or graph search – next lecture.

BFS

Algorithm		Complete	Optimal	Time	Space
DFS	w/ Path Checking	N unless finite	N	$O(b^m)$	$O(bm)$
BFS		Y	Y	$O(b^d)$	$O(b^d)$



Memory a Limitation?

- Suppose:
  - 4 GHz CPU
  - 32 GB main memory
  - 100 instructions / expansion
  - 5 bytes / node

- 40 M expansions / sec
  - Memory filled in … 3 min