CSE 573: Introduction to Artificial Intelligence

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Search
(Un-informed, Informed Search)

slides adapted from
Dan Klein, Pieter Abbeel ai.berkeley.edu
And Dan Weld, Luke Zettelmoyer
To Do:

- Check out PS1 in the webpage
  - Start ASAP
  - Submission: Canvas

- Website:
  - Do readings for search algorithms
  - Try this search visualization tool
    - http://qiao.github.io/PathFinding.js/visual/
Recap: Search
Recap: Search

- **Search problem:**
  - States (configurations of the world)
  - Actions and costs
  - Successor function (world dynamics)
  - Start state and goal test

- **Search tree:**
  - Nodes: represent plans for reaching states

- **Search algorithm:**
  - Systematically builds a search tree
  - Chooses an ordering of the fringe (unexplored nodes)
  - Optimal: finds least-cost plans
Depth-First Search

Strategy: expand a deepest node first

Implementation:
Fringe is a LIFO stack
Breadth-First Search

Strategy: expand a shallowest node first

Implementation: Fringe is a FIFO queue
## Search Algorithm Properties

<table>
<thead>
<tr>
<th>Algorithm</th>
<th>Complete</th>
<th>Optimal</th>
<th>Time</th>
<th>Space</th>
</tr>
</thead>
<tbody>
<tr>
<td>DFS</td>
<td>w/ Path Checking</td>
<td>Y</td>
<td>N</td>
<td>O($b^m$)</td>
</tr>
<tr>
<td>BFS</td>
<td></td>
<td>Y*</td>
<td>O($b^d$)</td>
<td>O($b^d$)</td>
</tr>
</tbody>
</table>

The diagram illustrates the growth of nodes in a tree structure with $d$ tiers. The number of nodes follows the pattern:

- 1 node
- $b$ nodes
- $b^2$ nodes
- $b^d$ nodes
- $b^m$ nodes

This visual representation complements the table, providing a clear depiction of the growth and distribution of nodes in the tree structure related to different search algorithms.
Video of Demo Maze Water DFS/BFS (part 1)
Video of Demo Maze Water DFS/BFS (part 2)
DFS vs BFS

- When will BFS outperform DFS?
- When will DFS outperform BFS?
Iterative Deepening

- Idea: get DFS’s space advantage with BFS’s time / shallow-solution advantages
  - Run a DFS with depth limit 1. If no solution...
  - Run a DFS with depth limit 2. If no solution...
  - Run a DFS with depth limit 3. ..... 

- Isn’t that wastefully redundant?
  - Generally most work happens in the lowest level searched, so not so bad!
Cost-Sensitive Search
BFS finds the shortest path in terms of number of actions. It does not find the least-cost path. We will now cover a similar algorithm which does find the least-cost path.
Uniform Cost Search
Uniform Cost Search

Strategy: expand a cheapest node first:

Fringe is a priority queue (priority: cumulative cost)
Uniform Cost Search (UCS) Properties

- What nodes does UCS expand?
  - Processes all nodes with cost less than cheapest solution!
  - If that solution costs $C^*$ and arcs cost at least $\varepsilon$, then the “effective depth” is roughly $C^*/\varepsilon$
  - Takes time $O(b^{C^*/\varepsilon})$ (exponential in effective depth)

- How much space does the fringe take?
  - Has roughly the last tier, so $O(b^{C^*/\varepsilon})$

- Is it complete?
  - Assuming best solution has a finite cost and minimum arc cost is positive, yes! (if no solution, still need depth $\neq \infty$)

- Is it optimal?
  - Yes! (Proof via A*)
Uniform Cost Issues

- Remember: UCS explores increasing cost contours

- The good: UCS is complete and optimal!

- The bad:
  - Explores options in every “direction”
  - No information about goal location

- We’ll fix that soon!
Video of Demo Empty UCS
Video of Demo Maze with Deep/Shallow Water --- DFS, BFS, or UCS? (part 1)
Video of Demo Maze with Deep/Shallow Water --- DFS, BFS, or UCS? (part 2)
Video of Demo Maze with Deep/Shallow Water --- DFS, BFS, or UCS? (part 3)
Example: Pancake Problem

Cost: Number of pancakes flipped
Example: Pancake Problem

BOUND FOR SORTING BY PREFIX REVERSAL

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Microsoft, Albuquerque, New Mexico

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Received 18 January 1978
Revised 28 August 1978

For a permutation $\sigma$ of the integers from 1 to $n$, let $f(\sigma)$ be the smallest number of prefix reversals that will transform $\sigma$ to the identity permutation, and let $f(n)$ be the largest such $f(\sigma)$ for all $\sigma$ in (the symmetric group) $S_n$. We show that $f(n) \leq (5n + 5)/3$, and that $f(n) \geq 17n/16$ for $n$ a multiple of 16. If, furthermore, each integer is required to participate in an even number of reversed prefixes, the corresponding function $g(n)$ is shown to obey $3n/2 - 1 \leq g(n) \leq 2n + 3$. 
Example: Pancake Problem

State space graph with costs as weights
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

Action: flip top two  
Cost: 2

Action: flip all four  
Cost: 4

Path to reach goal:  
Flip four, flip three
Total cost: 7
All these search algorithms are the same except for fringe strategies

- Conceptually, all fringes are priority queues (i.e. collections of nodes with attached priorities)
- Practically, for DFS and BFS, you can avoid the log(n) overhead from an actual priority queue, by using stacks and queues
- Can even code one implementation that takes a variable queuing object
Up next: Informed Search

- Uninformed Search
  - DFS
  - BFS
  - UCS

- Informed Search
  - Heuristics
  - Greedy Search
  - A* Search
  - Graph Search
Search Heuristics

- **A heuristic is:**
  - A function that *estimates* how close a state is to a goal
  - Designed for a particular search problem
  - Pathing?
  - Examples: Manhattan distance, Euclidean distance for pathing
Example: Heuristic Function

$h(x)$
Example: Heuristic Function

Heuristic: the number of the largest pancake that is still out of place
Greedy Search
Greedy Search

- Expand the node that seems closest...

- Is it optimal?
  - No. Resulting path to Bucharest is not the shortest!
Greedy Search

- **Strategy:** expand a node that you think is closest to a goal state
  - **Heuristic:** estimate of distance to nearest goal for each state

- **A common case:**
  - Best-first takes you straight to the (wrong) goal

- **Worst-case:** like a badly-guided DFS
Video of Demo Contours Greedy (Empty)
Video of Demo Contours Greedy (Pacman Small Maze)
A* Search
Combining UCS and Greedy

- **Uniform-cost** orders by path cost, or *backward cost* \( g(n) \)
- **Greedy** orders by goal proximity, or *forward cost* \( h(n) \)

\[ f(n) = g(n) + h(n) \]

Example: Teg Grenager
When should A* terminate?

- Should we stop when we enqueue a goal?

  No: only stop when we dequeue a goal.
Is A* Optimal?

- What went wrong?
  - Actual bad goal cost < estimated good goal cost
  - We need estimates to be less than actual costs!
Idea: Admissibility

Inadmissible (pessimistic) heuristics break optimality by trapping good plans on the fringe.

Admissible (optimistic) heuristics slow down bad plans but never outweigh true costs.
Admissible Heuristics

- A heuristic \( h \) is admissible (optimistic) if:

\[
0 \leq h(n) \leq h^*(n)
\]

where \( h^*(n) \) is the true cost to a nearest goal

- Examples:

- Coming up with admissible heuristics is most of what’s involved in using A* in practice.
Optimality of A* Tree Search
Optimality of A* Tree Search

Assume:
- A is an optimal goal node
- B is a suboptimal goal node
- h is admissible

Claim:
- A will exit the fringe before B
Optimality of A* Tree Search: Blocking

Proof:

- Imagine B is on the fringe
- Some ancestor $n$ of A is on the fringe, too (maybe A!)
- Claim: $n$ will be expanded before B
  1. $f(n)$ is less or equal to $f(A)$

\[
\begin{align*}
f(n) &= g(n) + h(n) & \text{Definition of f-cost} \\
f(n) &\leq g(A) & \text{Admissibility of h} \\
g(A) &= f(A) & h = 0 \text{ at a goal}
\end{align*}
\]
Proof:
- Imagine B is on the fringe
- Some ancestor \( n \) of A is on the fringe, too (maybe A!)
- Claim: \( n \) will be expanded before B
  1. \( f(n) \) is less or equal to \( f(A) \)
  2. \( f(A) \) is less than \( f(B) \)

\[ g(A) < g(B) \quad \text{B is suboptimal} \]
\[ f(A) < f(B) \quad \text{h = 0 at a goal} \]
Proof:
- Imagine B is on the fringe
- Some ancestor n of A is on the fringe, too (maybe A!)
- Claim: n will be expanded before B
  1. $f(n)$ is less or equal to $f(A)$
  2. $f(A)$ is less than $f(B)$
  3. n expands before B
- All ancestors of A expand before B
- A expands before B
- A* search is optimal
Properties of A*

Uniform-Cost

A*
UCS vs A* Contours

- Uniform-cost expands equally in all “directions”

- A* expands mainly toward the goal, but does hedge its bets to ensure optimality
Video of Demo Contours (Empty) – A*
Video of Demo Contours (Pacman Small Maze) – A*
Comparison

Greedy

Uniform Cost

A*
Which algorithm?
Which algorithm?
Video of Demo Empty Water Shallow/Deep – Guess Algorithm
A*: Summary

- A* uses both backward costs and (estimates of) forward costs
- A* is optimal with admissible (optimistic) heuristics
- Heuristic design is key: often use relaxed problems
Creating Heuristics
Creating Admissible Heuristics

- Most of the work in solving hard search problems optimally is in coming up with admissible heuristics.
- Often, admissible heuristics are solutions to relaxed problems, where new actions are available.
- Inadmissible heuristics are often useful too.
Example: 8 Puzzle

- What are the states?
- How many states?
- What are the actions?
- How many successors from the start state?
- What should the costs be?

Start State

Goal State

Admissible heuristics?
8 Puzzle I

- Heuristic: Number of tiles misplaced
- Why is it admissible?
- $h(\text{start}) = 8$
- This is a relaxed-problem heuristic

Start State

Goal State

Statistics from Andrew Moore
8 Puzzle II

- What if we had an easier 8-puzzle where any tile could slide any direction at any time, ignoring other tiles?

- Total Manhattan distance

- Why is it admissible?

- \( h(\text{start}) = 3 + 1 + 2 + \ldots = 18 \)

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### Average nodes expanded when the optimal path has...

<table>
<thead>
<tr>
<th></th>
<th>...4 steps</th>
<th>...8 steps</th>
<th>...12 steps</th>
</tr>
</thead>
<tbody>
<tr>
<td>TILES</td>
<td>13</td>
<td>39</td>
<td>227</td>
</tr>
<tr>
<td>MANHATTAN</td>
<td>12</td>
<td>25</td>
<td>73</td>
</tr>
</tbody>
</table>
8 Puzzle III

- How about using the *actual cost* as a heuristic?
  - Would it be admissible?
  - Would we save on nodes expanded?
  - What’s wrong with it?

- With A*: a trade-off between quality of estimate and work per node
  - As heuristics get closer to the true cost, you will expand fewer nodes but usually do more work per node to compute the heuristic itself
Semi-Lattice of Heuristics
Trivial Heuristics, Dominance

- **Dominance**: \( h_a \geq h_c \) if
  \[
  \forall n : h_a(n) \geq h_c(n)
  \]

- **Heuristics form a semi-lattice**:
  - Max of admissible heuristics is admissible
    \[
    h(n) = \max(h_a(n), h_b(n))
    \]

- **Trivial heuristics**
  - Bottom of lattice is the zero heuristic
    (what does this give us?)
  - Top of lattice is the exact heuristic
Graph Search
Tree Search: Extra Work!

- Failure to detect repeated states can cause exponentially more work.
In BFS, for example, we shouldn’t bother expanding the circled nodes (why?)
Graph Search

- Idea: never expand a state twice

- How to implement:
  - Tree search + set of expanded states ("closed set")
  - Expand the search tree node-by-node, but...
  - Before expanding a node, check to make sure its state has never been expanded before
  - If not new, skip it, if new add to closed set

- Important: store the closed set as a set, not a list

- Can graph search wreck completeness? Why/why not?

- How about optimality?
A* Graph Search Gone Wrong?

State space graph

Search tree

Closed Set: S B C A
Consistency of Heuristics

- **Main idea:** estimated heuristic costs ≤ actual costs
  - Admissibility: heuristic cost ≤ actual cost to goal
    \[ h(A) \leq \text{actual cost from } A \text{ to } G \]
  - Consistency: heuristic “arc” cost ≤ actual cost for each arc
    \[ h(A) - h(C) \leq \text{cost}(A \text{ to } C) \]

- **Consequences of consistency:**
  - The f value along a path never decreases
    \[ g(A) + h(A) \leq \text{cost}(A \text{ to } C) + h(C) \]
  - A* graph search is optimal
A* Graph Search

Sketch: consider what A* does with a consistent heuristic:

- Fact 1: In tree search, A* expands nodes in increasing total f value (f-contours)
- Fact 2: For every state s, nodes that reach s optimally are expanded before nodes that reach s suboptimally
- Result: A* graph search is optimal
Optimality

- **Tree search:**
  - A* is optimal if heuristic is admissible
  - UCS is a special case (h = 0)

- **Graph search:**
  - A* optimal if heuristic is consistent
  - UCS optimal (h = 0 is consistent)

- Consistency implies admissibility

- In general, most natural admissible heuristics tend to be consistent, especially if from relaxed problems
Pseudo-Code

function Tree-Search(problem, fringe) return a solution, or failure
    fringe ← INSERT(MAKE-NODE(INITIAL-STATE[problem]), fringe)
    loop do
        if fringe is empty then return failure
        node ← REMOVE-FRONT(fringe)
        if GOAL-TEST(problem, STATE[node]) then return node
        for child-node in EXPAND(STATE[node], problem) do
            fringe ← INSERT(child-node, fringe)
        end
    end
end

function Graph-Search(problem, fringe) return a solution, or failure
    closed ← an empty set
    fringe ← INSERT(MAKE-NODE(INITIAL-STATE[problem]), fringe)
    loop do
        if fringe is empty then return failure
        node ← REMOVE-FRONT(fringe)
        if GOAL-TEST(problem, STATE[node]) then return node
        if STATE[node] is not in closed then
            add STATE[node] to closed
            for child-node in EXPAND(STATE[node], problem) do
                fringe ← INSERT(child-node, fringe)
            end
        end
    end
A* Applications

- Video games
- Pathing / routing problems
- Resource planning problems
- Robot motion planning
- Language analysis
- Machine translation
- Speech recognition
- …
A* in Recent Literature

- Joint A* CCG Parsing and Semantic Role Labeling (EMLN’15)
- Diagram Understanding (ECCV’17)
Search and Models

- Search operates over models of the world
  - The agent doesn’t actually try all the plans out in the real world!
  - Planning is all “in simulation”
- Your search is only as good as your models…
Search Gone Wrong?