CSE 573: Introduction to Artificial Intelligence

Hanna Hajishirzi

Search
(Un-informed, Informed Search)

slides adapted from
Dan Klein, Pieter Abbeel ai.berkeley.edu
And Dan Weld, Luke Zettelmoyer
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
Example: Pancake Problem

Cost: Number of pancakes flipped
Example: Pancake Problem

BOUNDS FOR SORTING BY PREFIX REVERSAL

William H. GATES
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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

Path to reach goal:  
Flip four, flip three  
Total cost: 7
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!
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
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  - A* Search
  - Graph Search
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
A* Search

UCS

Greedy
Combining UCS and Greedy

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

A* Search orders by the sum: $f(n) = g(n) + h(n)$

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.
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.
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
Comparison

Greedy  Uniform Cost  A*
Video of Demo Contours (Empty) -- UCS
Video of Demo Contours (Empty) -- Greedy
Video of Demo Contours (Empty) – A*
Video of Demo Contours (Pacman Small Maze) – A∗
Which algorithm?
Which algorithm?
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 $f(A)$

\[
 f(n) = g(n) + h(n) \quad \text{Definition of f-cost}
\]
\[
 f(n) \leq g(A) \quad \text{Admissibility of h}
\]
\[
 g(A) = f(A) \quad h = 0 \text{ at a goal} 
\]
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 \( f(A) \)
  2. \( f(A) \) is less than \( f(B) \)

\[ g(A) < g(B) \]
\[ f(A) < f(B) \]

B is suboptimal
\[ h = 0 \text{ at a goal} \]
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

$f(n) \leq f(A) < f(B)$
A*: Summary
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
Video of Demo Empty Water Shallow/Deep – Guess Algorithm
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?

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

<table>
<thead>
<tr>
<th>Start State</th>
<th>Goal State</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 2 3</td>
<td>1 2</td>
</tr>
<tr>
<td>4 5 6</td>
<td>3 4 5</td>
</tr>
<tr>
<td>7 8</td>
<td>6 7 8</td>
</tr>
</tbody>
</table>

---

Statistics from Andrew Moore

<table>
<thead>
<tr>
<th>Average nodes expanded when the optimal path has...</th>
<th>UCS</th>
<th>TILES</th>
</tr>
</thead>
<tbody>
<tr>
<td>...4 steps</td>
<td>112</td>
<td>13</td>
</tr>
<tr>
<td>...8 steps</td>
<td>6,300</td>
<td>39</td>
</tr>
<tr>
<td>...12 steps</td>
<td>$3.6 \times 10^6$</td>
<td>227</td>
</tr>
</tbody>
</table>
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?

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

<table>
<thead>
<tr>
<th>TILES</th>
<th>4 steps</th>
<th>8 steps</th>
<th>12 steps</th>
</tr>
</thead>
<tbody>
<tr>
<td>13</td>
<td>12</td>
<td>227</td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>MANHATTAN</th>
<th>4 steps</th>
<th>8 steps</th>
<th>12 steps</th>
</tr>
</thead>
<tbody>
<tr>
<td>12</td>
<td>25</td>
<td>73</td>
<td></td>
</tr>
</tbody>
</table>
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
A*: Summary
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
Graph Search
Tree Search: Extra Work!

- Failure to detect repeated states can cause exponentially more work.
Graph Search

- 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
    \[ h(A) \leq \text{actual cost from A to G} \]
  - **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
    \[ f(A) \leq g(A) + h(A) \leq g(A) + (\text{cost}(A \text{ to C}) + h(C)) \]
  - 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 of A* Search

- With a admissible heuristic, Tree A* is optimal.
- With a consistent heuristic, Graph A* is optimal.
- With h=0, the same proof shows that UCS is optimal.
**Pseudo-Code**

```plaintext
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
end
```
A* Applications

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

- Joint A* CCG Parsing and Semantic Role Labeling (EMNLP’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?