Problem solving and search: Chapter 3, Sections 1–5

Outline

- ♢ Problem-solving agents
- ♢ Problem types
- ♢ Problem formulation
- ♢ Example problems
- ♢ Basic search algorithms

Problem-solving agents

Restricted form of general agent:


```
function SIMPLE-PROBLEM-SOLVING-AGENT(percept) returns an action
  static: seq, an action sequence, initially empty
          state, some description of the current world state
          goal, a goal, initially null
          problem, a problem formulation

  state ← UPDATE-STATE(state, percept)
  if seq is empty then
      goal ← FORMULATE-GOAL(state)
      problem ← FORMULATE-PROBLEM(state, goal)
      seq ← SEARCH(problem)
  action ← RECOMMENDATION(seq, state)
  seq ← REMAINDER(seq, state)
  return action
```

Note: this is *offline* problem solving; solution executed "eyes closed."
Online problem solving involves acting without complete knowledge.

Example: Romania

On holiday in Romania; currently in Arad.
Flight leaves tomorrow from Bucharest

Formulate goal:

be in Bucharest

Formulate problem:

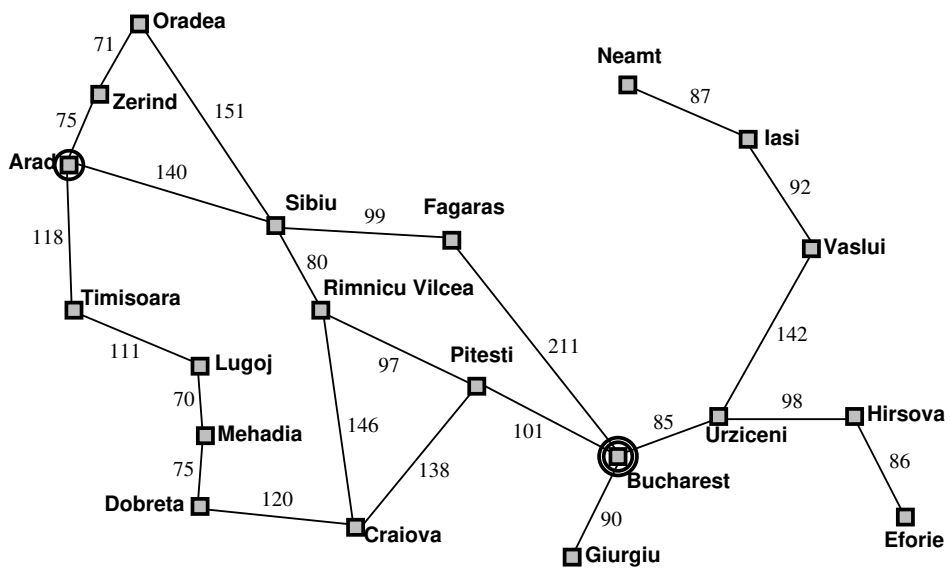
states: various cities

actions: drive between cities

Find solution:

sequence of cities, e.g., Arad, Sibiu, Fagaras, Bucharest

Example: Romania



Problem types

Deterministic, fully observable $\Longrightarrow$ *single-state problem*

Agent knows exactly which state it will be in; solution is a sequence

Non-observable $\Longrightarrow$ *conformant problem*

Agent may have no idea where it is; solution (if any) is a sequence

Nondeterministic and/or partially observable $\Longrightarrow$ *contingency problem*

percepts provide *new* information about current state

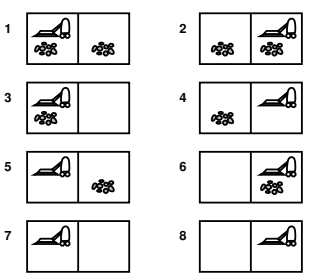
solution is a *tree* or *policy*

often *interleave* search, execution

Unknown state space $\Longrightarrow$ *exploration problem* ("online")

Example: vacuum world

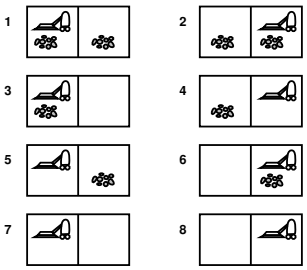
Single-state, start in #5. Solution??



Example: vacuum world

Single-state, start in #5. Solution??
$[Right, Suck]$

Conformant, start in $\{1, 2, 3, 4, 5, 6, 7, 8\}$
e.g., $Right$ goes to $\{2, 4, 6, 8\}$. Solution??



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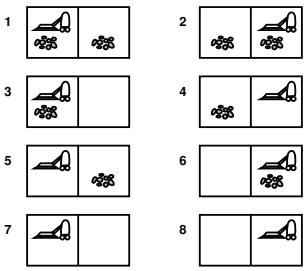
$[Right, Suck, Left, Suck]$

Contingency, start in #5
Murphy's Law: $Suck$ can dirty a clean carpet
Local sensing: dirt, location only.
Solution??



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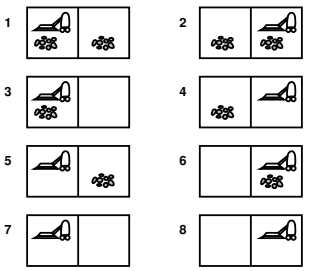
Contingency, start in #5
Murphy's Law: $Suck$ can dirty a clean carpet
Local sensing: dirt, location only.
Solution??
$[Right, \textbf{if } dirt \textbf{ then } Suck]$



Single-state problem formulation

A *problem* is defined by four items:

initial state e.g., "at Arad"

successor function $S(x)$ = set of action–state pairs
e.g., $S(Arad) = \{< Arad \rightarrow Zerind, Zerind >, \ldots\}$

goal test, can be
explicit, e.g., x = "at Bucharest"
implicit, e.g., $NoDirt(x)$

path cost (additive)
e.g., sum of distances, number of actions executed, etc.
$c(x, a, y)$ is the step cost, assumed to be ≥ 0

A *solution* is a sequence of actions
leading from the initial state to a goal state

Selecting a state space

Real world is absurdly complex

$\Rightarrow$ state space must be *abstracted* for problem solving

(Abstract) state = set of real states

(Abstract) action = complex combination of real actions

e.g., "Arad $\rightarrow$ Zerind" represents a complex set of possible routes, detours, rest stops, etc.

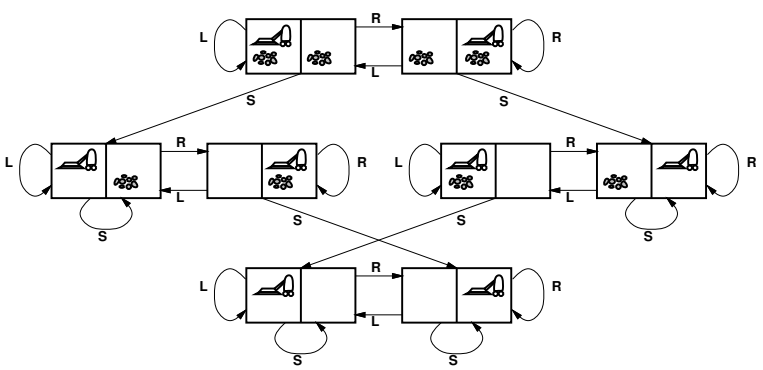
For guaranteed realizability, any real state "in Arad" must get to *some* real state "in Zerind"

(Abstract) solution =

set of real paths that are solutions in the real world

Each abstract action should be "easier" than the original problem!

Example: vacuum world state space graph



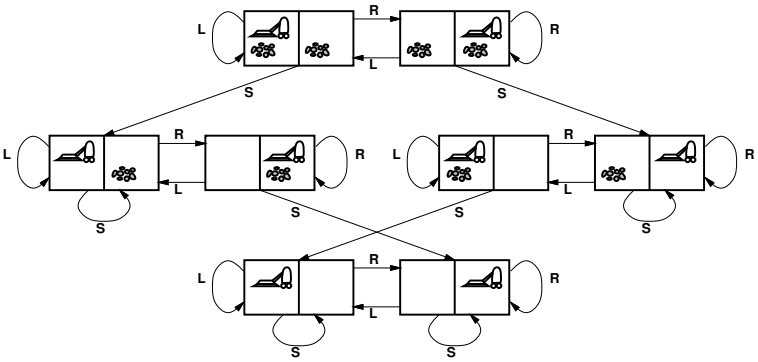
states??

actions??

goal test??

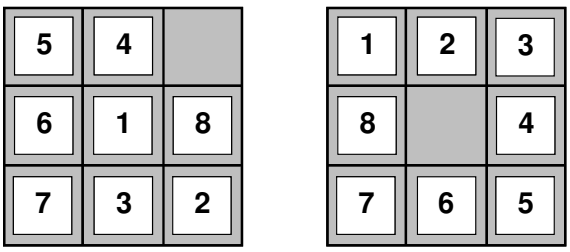
path cost??

Example: vacuum world state space graph



states??: integer dirt and robot locations (ignore dirt *amounts*)
actions??: $Left$, $Right$, $Suck$, $NoOp$
goal test??: no dirt
path cost??: 1 per action (0 for $NoOp$)

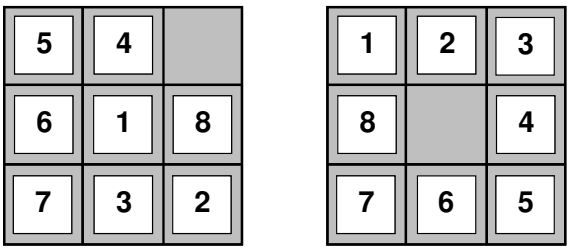
Example: The 8-puzzle



Start State Goal State

states??
actions??
goal test??
path cost??

Example: The 8-puzzle



states??: integer locations of tiles (ignore intermediate positions)

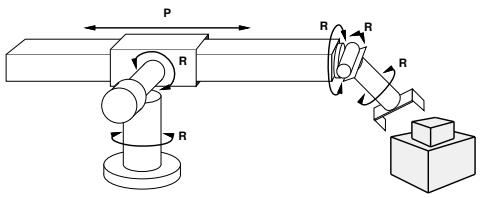
actions??: move blank left, right, up, down (ignore unjamming etc.)

goal test??: = goal state (given)

path cost??: 1 per move

[Note: optimal solution of n-Puzzle family is NP-hard]

Example: robotic assembly



states??: real-valued coordinates of
robot joint angles
parts of the object to be assembled

actions??: continuous motions of robot joints

goal test??: complete assembly *with no robot included!*

path cost??: time to execute

Tree search algorithms

Basic idea:

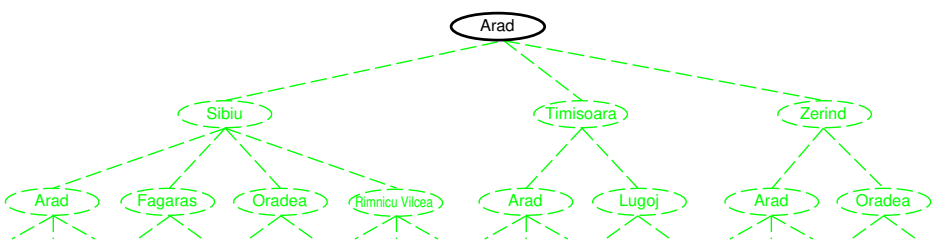
offline, simulated exploration of state space

by generating successors of already-explored states

(a.k.a. *expanding* states)

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

Tree search example



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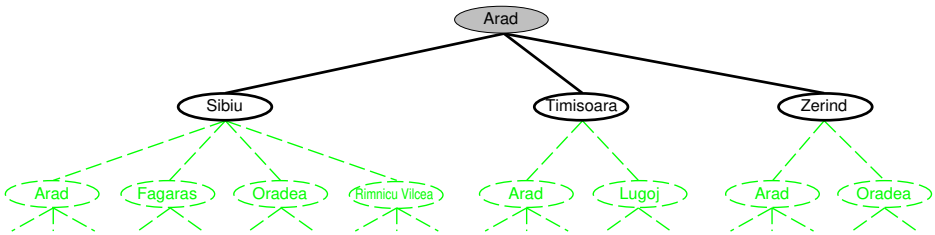

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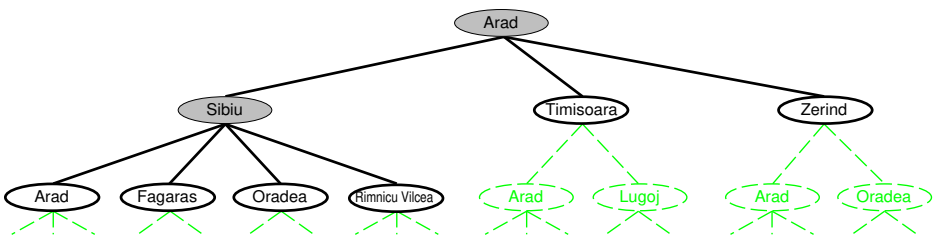


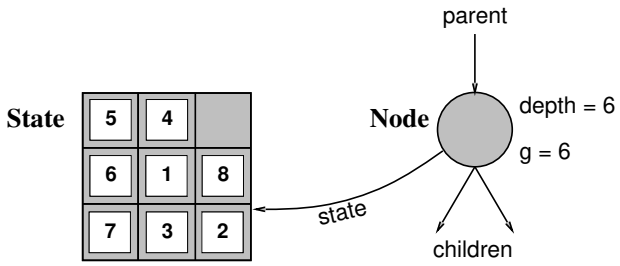
Implementation: states vs. nodes

A *state* is a (representation of) a physical configuration

A *node* is a data structure constituting part of a search tree

includes *parent*, *children*, *depth*, *path cost* $g(x)$

States do not have parents, children, depth, or path cost!



The EXPAND function creates new nodes, filling in the various fields and using the SUCCESSORFN of the problem to create the corresponding states.

Implementation: general tree search

```
function TREE-SEARCH( problem, fringe) returns 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] applied to STATE(node) succeeds return node
    fringe ← INSERTALL(EXPAND(node, problem), fringe)

function EXPAND( node, problem) returns a set of nodes
  successors ← the empty set
  for each action, result in SUCCESSOR-FN[problem](STATE[node]) do
    s ← a new NODE
    PARENT-NODE[s] ← node;  ACTION[s] ← action;  STATE[s] ← result
    PATH-COST[s] ← PATH-COST[node] + STEP-COST(node, action, s)
    DEPTH[s] ← DEPTH[node] + 1
    add s to successors
  return successors
```

Search strategies

A strategy is defined by picking the *order of node expansion*

Strategies are evaluated along the following dimensions:

completeness—does it always find a solution if one exists?
time complexity—number of nodes generated/expanded
space complexity—maximum number of nodes in memory
optimality—does it always find a least-cost solution?

Time and space complexity are measured in terms of

b—maximum branching factor of the search tree
d—depth of the least-cost solution
m—maximum depth of the state space (may be ∞)

Uninformed search strategies

Uninformed strategies use only the information available in the problem definition

Breadth-first search

Uniform-cost search

Depth-first search

Depth-limited search

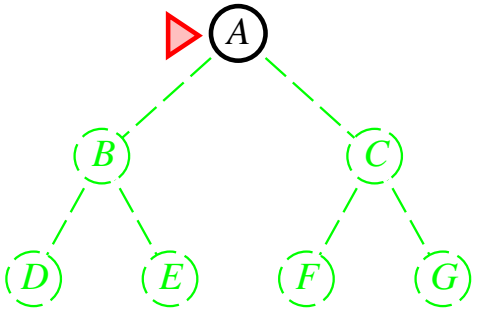
Iterative deepening search

Breadth-first search

Expand shallowest unexpanded node

Implementation:

fringe is a FIFO queue, i.e., new successors go at end



Breadth-first search

Expand shallowest unexpanded node

Implementation:

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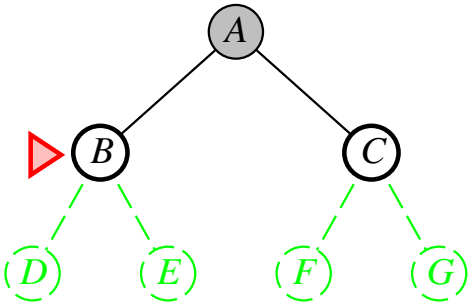

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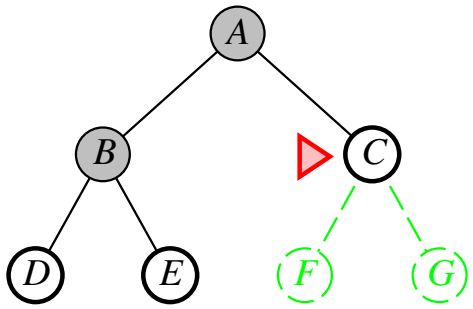

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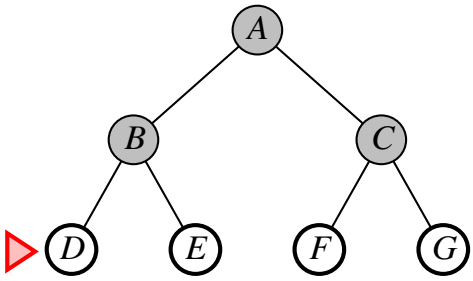

Properties of breadth-first search

Complete??

Properties of breadth-first search

Complete?? Yes (if b is finite)

Time??

Properties of breadth-first search

Complete?? Yes (if b is finite)

Time?? $1 + b + b^2 + b^3 + \ldots + b^d + b(b^d - 1) = O(b^{d+1})$, i.e., exp. in d

Space??

Properties of breadth-first search

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Time?? $1 + b + b^2 + b^3 + \ldots + b^d + b(b^d - 1) = O(b^{d+1})$, i.e., exp. in d

Space?? $O(b^{d+1})$ (keeps every node in memory)

Optimal??

Properties of breadth-first search

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Space?? $O(b^{d+1})$ (keeps every node in memory)

Optimal?? Yes (if cost = 1 per step); not optimal in general

Space is the big problem; can easily generate nodes at 10MB/sec
so 24hrs = 860GB.

Uniform-cost search

Expand least-cost unexpanded node

Implementation:
fringe = queue ordered by path cost

Equivalent to breadth-first if step costs all equal

Complete?? Yes, if step cost $\geq \epsilon$

Time?? # of nodes with $g \leq$ cost of optimal solution, $O(b^{\lceil C^*/\epsilon \rceil})$
where C^* is the cost of the optimal solution

Space?? # of nodes with $g \leq$ cost of optimal solution, $O(b^{\lceil C^*/\epsilon \rceil})$

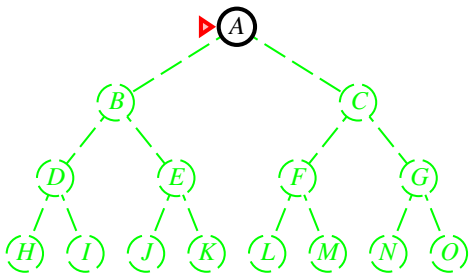
Optimal?? Yes—nodes expanded in increasing order of $g(n)$

Depth-first search

Expand deepest unexpanded node

Implementation:

fringe = LIFO queue, i.e., put successors at front



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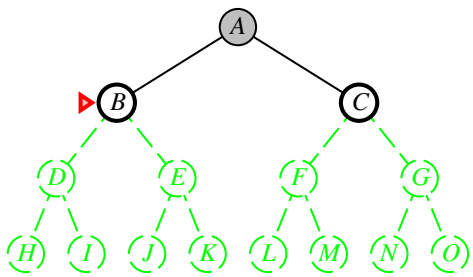

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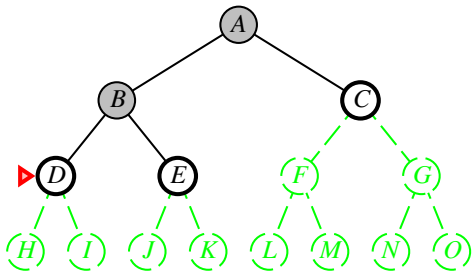

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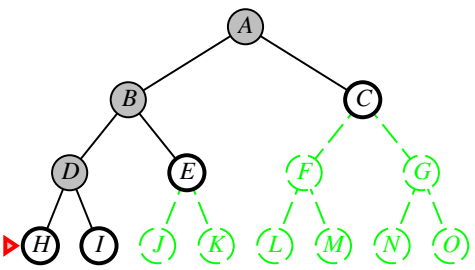

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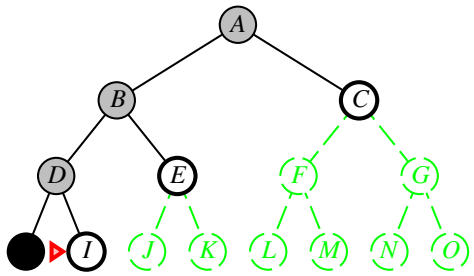

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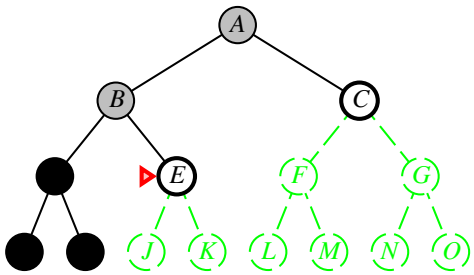

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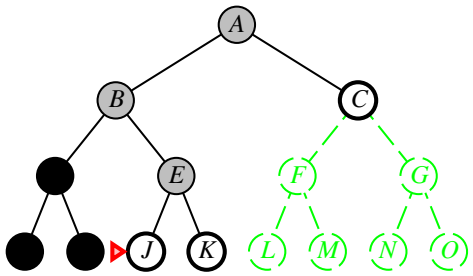

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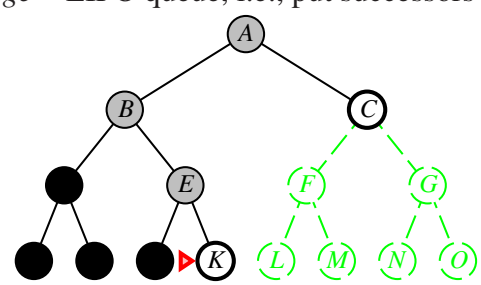

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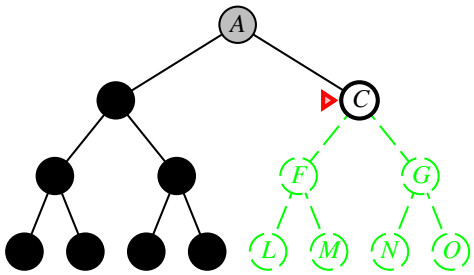

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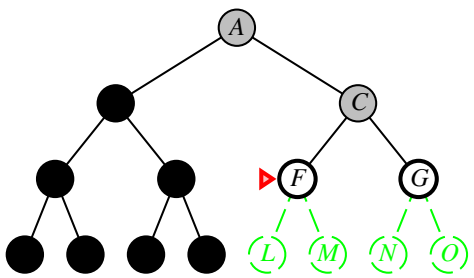

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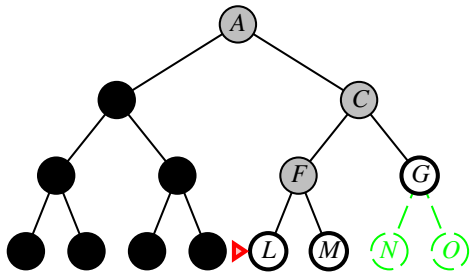

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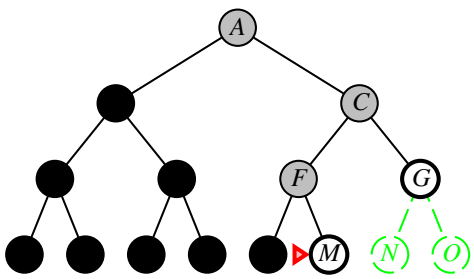

Properties of depth-first search

Complete??

Properties of depth-first search

Complete?? No: fails in infinite-depth spaces, spaces with loops

Modify to avoid repeated states along path

$\Rightarrow$ complete in finite spaces

Time??

Properties of depth-first search

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Modify to avoid repeated states along path
$\Rightarrow$ complete in finite spaces

Time?? $O(b^m)$: terrible if m is much larger than d
but if solutions are dense, may be much faster than breadth-first

Space??

Properties of depth-first search

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Modify to avoid repeated states along path
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Time?? $O(b^m)$: terrible if m is much larger than d
but if solutions are dense, may be much faster than breadth-first

Space?? $O(bm)$, i.e., linear space!

Optimal??

Properties of depth-first search

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Modify to avoid repeated states along path
$\Rightarrow$ complete in finite spaces

Time?? $O(b^m)$: terrible if m is much larger than d
but if solutions are dense, may be much faster than breadth-first

Space?? $O(bm)$, i.e., linear space!

Optimal?? No

Depth-limited search

= depth-first search with depth limit l,
i.e., nodes at depth l have no successors

Recursive implementation:

```
function DEPTH-LIMITED-SEARCH( problem, limit) returns soln/fail/cutoff
  RECURSIVE-DLS(MAKE-NODE(INITIAL-STATE[problem]), problem, limit)

function RECURSIVE-DLS(node, problem, limit) returns soln/fail/cutoff
  cutoff-occurred? ← false
  if GOAL-TEST[problem](STATE[node]) then return node
  else if DEPTH[node] = limit then return cutoff
  else for each successor in EXPAND(node, problem) do
      result ← RECURSIVE-DLS(successor, problem, limit)
      if result = cutoff then cutoff-occurred? ← true
      else if result ≠ failure then return result
  if cutoff-occurred? then return cutoff else return failure
```

Iterative deepening search

```
function ITERATIVE-DEEPENING-SEARCH(problem) returns a solution sequence
  inputs: problem, a problem

  for depth ← 0 to ∞ do
    result ← DEPTH-LIMITED-SEARCH(problem, depth)
    if result ≠ cutoff then return result
  end
```


Iterative deepening search $l = 0$

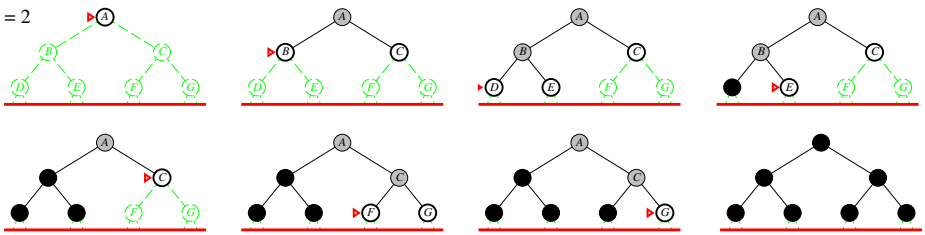
Limit = 0

Iterative deepening search $l = 1$

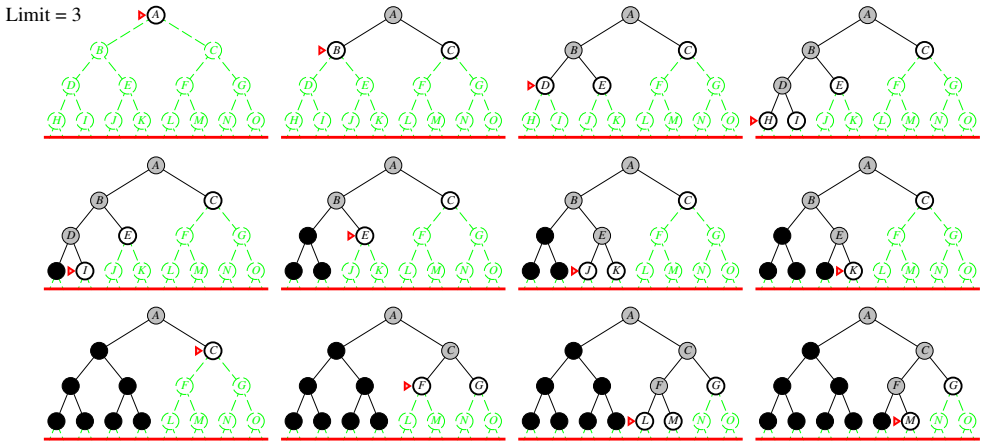
Limit = 1

Iterative deepening search $l = 2$

Limit = 2



Iterative deepening search $l = 3$



Properties of iterative deepening search

Complete??

Properties of iterative deepening search

Complete?? Yes

Time??

Properties of iterative deepening search

Complete?? Yes

Time?? $(d+1)b^0 + db^1 + (d-1)b^2 + \ldots + b^d = O(b^d)$

Space??

Properties of iterative deepening search

Complete?? Yes

Time?? $(d+1)b^0 + db^1 + (d-1)b^2 + \ldots + b^d = O(b^d)$

Space?? $O(bd)$

Optimal??

Properties of iterative deepening search

Complete?? Yes

Time?? $(d+1)b^0 + db^1 + (d-1)b^2 + \ldots + b^d = O(b^d)$

Space?? $O(bd)$

Optimal?? Yes, if step cost = 1

Can be modified to explore uniform-cost tree

Numerical comparison for $b = 10$ and $d = 5$, solution at far right:

$$N(\text{IDS}) = 50 + 400 + 3,000 + 20,000 + 100,000 = 123,450$$

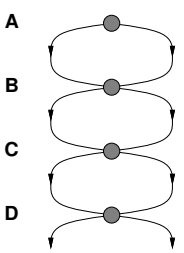
$$N(\text{BFS}) = 10 + 100 + 1,000 + 10,000 + 100,000 + 999,990 = 1,111,100$$

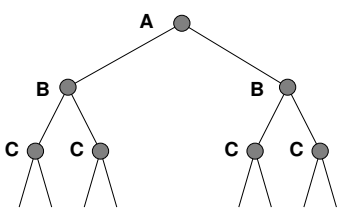
Summary of algorithms

Criterion	Breadth-First	Uniform-Cost	Depth-First	Depth-Limited	Iterative Deepening
Complete?	Yes*	Yes*	No	Yes, if $l \geq d$	Yes
Time	b^{d+1}	$b^{\lceil C^*/\epsilon \rceil}$	b^m	b^l	b^d
Space	b^{d+1}	$b^{\lceil C^*/\epsilon \rceil}$	bm	bl	bd
Optimal?	Yes*	Yes*	No	No	Yes

Repeated states

Failure to detect repeated states can turn a linear problem into an exponential one!





Graph search

```
function GRAPH-SEARCH( problem, fringe) returns 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
          fringe ← INSERTALL(EXPAND(node, problem), fringe)
  end
```


Summary

Problem formulation usually requires abstracting away real-world details to define a state space that can feasibly be explored

Variety of uninformed search strategies

Iterative deepening search uses only linear space
and not much more time than other uninformed algorithms