

Planning Representation: Preferences in PDDL

Objectives

Specific Objectives

- Model in PDDL 3.0
- Comparison with NASA planning language

Source

- Gerevini & Long. Plan Constraints and Preferences in PDDL₃. Technical Report, Department of Electronics for Automation, University of Brescia, Italy, August 2005

Outline

- **Introduction**
- Preferences in Planning
- PDDL 3 syntax
- PDDL₃ examples
- XIDDL language
- XIDDL example
- Conclusions

Introduction

- PDDL₂.X is still restrictive
 - Plan quality measured by plan size
 - Hard constraints on actions
 - Hard constraints on goals
- If not satisfied, NO plan!!
- Plan with soft constraints & goals
 - Best quality plan satisfy “as much as possible” the soft constraints & goals
- PDDL₂.X is extended: PDDL₃

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Preferences in planning (I)

- Transportation example
 - We would like that every airplane is used (instead of using only a few airplanes, because it is better to distribute the workload among the available resources and limit heavy usage)
 - Whenever a ship is ready at a port to load the containers it has to transport, all such containers should be ready at that port
 - We would like that at the end of the plan all trucks are clean and at their source location
 - We would like no truck to visit any destination more than once

Preferences in planning (II)

- Can express that certain plans are more preferred than others
 - *I prefer a plan where every airplane is used, rather than a plan using 100 units of fuel less,* which could be expressed by weighting a failure to use all the planes by a number 100 times bigger than the weight associated with the fuel use in the plan metric
 - *I prefer a plan where each city is visited at most once, rather than a plan with a shorter makespan,* which could be expressed by using constraint violation costs penalising a failure to visit each city at most once very heavily
 - *I prefer a plan where at the end each truck is at its start location, rather than a plan where every city is visited by at most one truck,* which could be expressed by using goal costs penalising a goal failure of having every truck at its start location more heavily than a failure of having in the plan every city visited by at most one truck

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PDDL syntax: Domain

```
(define (domain name)
  (:requirements <require-key> :constraints :preferences)
  (:types <typed_list (name)>)
  <PDDL list of predicates in the domain>
  <PDDL list of functions in the domain>
  <PDDL code for first action>
  ...
  <PDDL code for last action>
)
```

PDDL syntax: Problem

```
(define (problem <problem name>)
```

```
...
```

```
(preference [name] <GD>)
```

```
(:constraints
```

```
  (at end <GD>) | (always <GD>) | (sometime <GD>) | (within <num> <GD>) | (at-most-  
once <GD>) | (sometime-after <GD> <GD>) | (sometime-before <GD> <GD>) | (always-  
within <num> <GD> <GD>) | (hold-during <num> <num> <GD>) | (hold-after <num>  
<GD> | ...
```

```
  (is-violated <preference-name>)
```

```
)
```

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PDDL₃ examples: Preferences

- (preference VisitParis (forall (?x - tourist) (sometime (at ?x Paris))))
 - yields a violation count of 1 for (is-violated VisitParis), if at least one tourist fails to visit Paris
- (forall (?x - tourist) (preference VisitParis (sometime (at ?x Paris))))
 - yields a violation count equal to the number of people who failed to visit Paris
- (:goal (and (at package1 London) (preference p1 (clean truck1))))

PDDL₃ examples: Constraints

- Constraints can be used to weighted expressions in metrics
(:metric minimize (+ (* 10 (fuel-used)) (is-violated VisitParis)))
would weight fuel use as ten times more significant than violations of the VisitParis constraint
- Another example of multiple ones:
(:constraints (and (preference p1 (always (clean truck1))) (preference p2 (and (at end (at package2 Paris)) (sometime (clean track1)))) (preference p3 (...)) ...))
- Combine metrics and preferences
(:metric (+ (* 10 (is-violated p1)) (* 5 (is-violated p2)) (is-violated p3)))

Outline

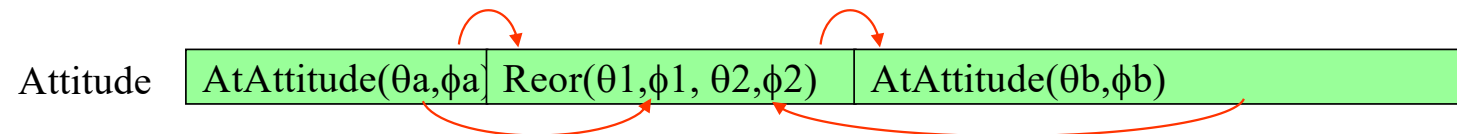
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XIDDL

- Declarative descriptions of legal operations of a system
- Models define:
 - Timelines: discrete state variables, populated over all time by predicates
 - Predicates/Tokens: parameterized state values that remain fixed over time intervals
 - Constraints: temporal and parameter restrictions between tokens/predicates

XIDDL

- What do we mean by a model?
 - For example, a spacecraft reorientation maneuver
 - MET_BY(Reor, AtAttitude) w/ $\theta_I = \theta_a, \phi_I = \phi_a$
 - MEETS(Reor, AtAttitude) w/ $\theta_2 = \theta_b, \phi_2 = \phi_b$



- Models written in XML-based language
- Enables automatic syntactic and semantic checking of model

XIDDL: domain (I)

- Timeline (TL) is a logical structure used to represent states over time
- Class is a set of TLs
- Types:
 - *Internal modes*: describes the internal state of the controlled subsystem. State transitions are not communicated outside
 - *Goal*: represents a system which exerts control over the agent itself
 - *Executable*: describes the state that will be communicated to the outside world when the state transition is at the current time

XIDDL: domain (II)

- Tokens/predicates: define the possible values that TLs can have:

$$P(i_1, \dots, i_n \rightarrow m_1, \dots, m_k \rightarrow o_1, \dots, o_m; s)$$

Each i_i , m_i y o_i represents: input arguments, mode and output argument

- Types:
 - *call_args*: are passed to the external system
 - *internal_modes*: set for internal reasoning and not to communicate out
 - *return_args*: returned by the external subsystem
 - *return_status*: returned by the external subsystem and used for close loop
- Constraints: temporal and parameter restrictions between tokens

XIDDL: problem

- Specify what token exists in the initial state in each TL
- Generally the goals are loaded in a different module

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Space Operator domain (PDDL)

```
(:action take_image
  :parameters (?s - satellite ?d - direction
               ?i - instrument ?m - mode)
  :precondition (and (calibrated ?i)
                     (on_board ?i ?s)
                     (supports ?i ?m)
                     (power_on ?i)
                     (pointing ?s ?d)
                     (power_on ?i))
  :effect (have_image ?d ?m))
```

Space Operator problem (PDDL)

```
(:objects
  satelliteo satelliter satellite2- satellite
  instrumento instrumenti instrument2 - instrument
  ...
  Phenomenon4 Star5 Phenomenon6 – direction)

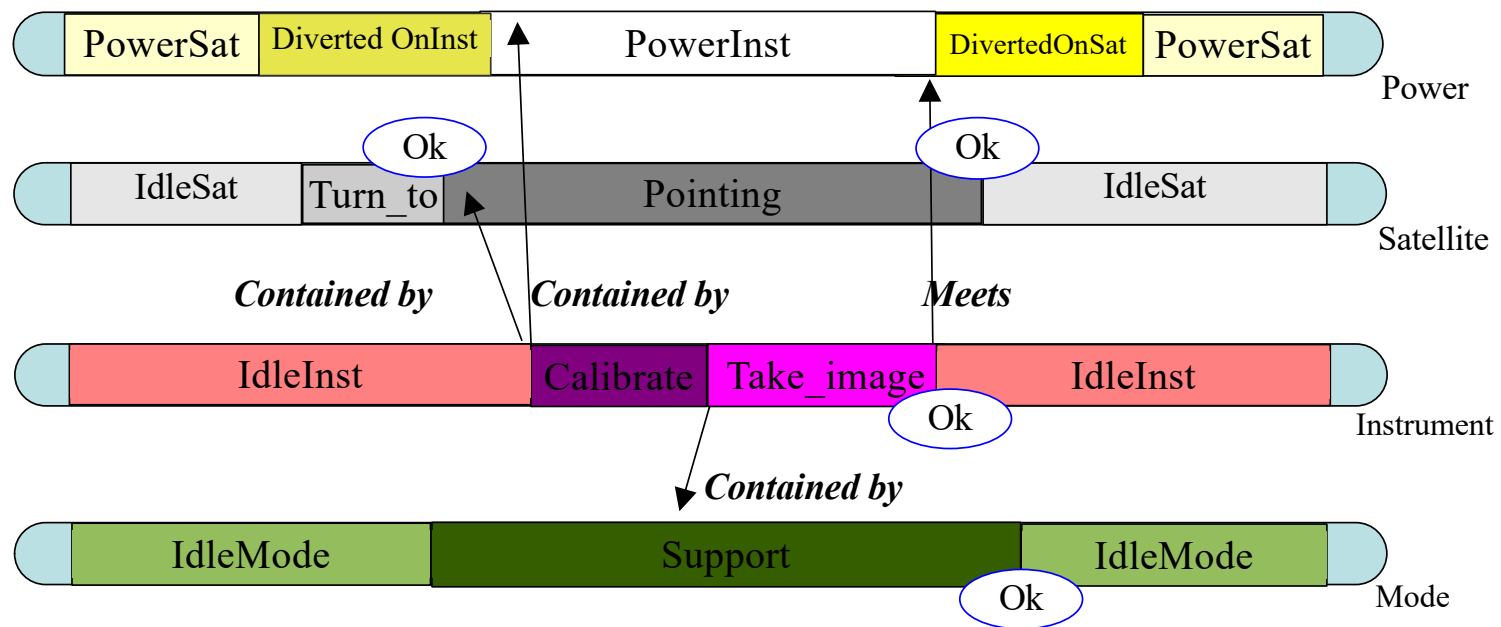
(:init
  (supports instrumento thermographo)
  (calibration_target instrumento GroundStation2)
  ...
  (pointing satelliteo Phenomenon6))

(:goal  (have_image Phenomenon4 thermographo)
        (have_image Star5 thermographo)
        (have_image Phenomenon6 thermographo))
```

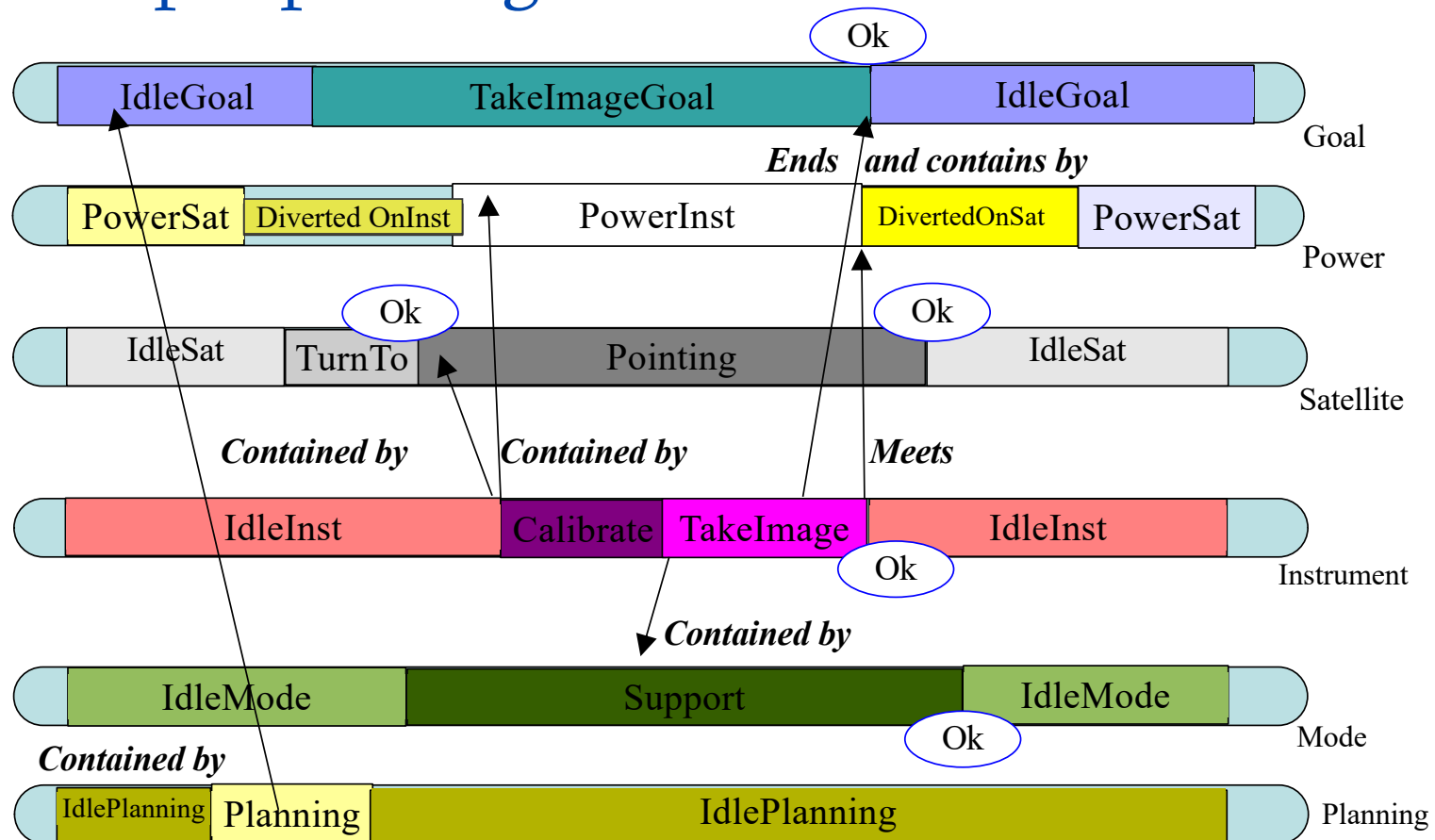
XIDDL example

- How to represent this information?
- What system do I want to know its evolution?
- How many TLs do I need?

XIDDL example: domain



XIDDL example: plan & goals



XIDDL: Domain

- TLs
 - satellite_TL
 - instrument_TL
 - power_TL
 - mode_TL

XIDDL: Domain

- Procedures
 - satellite_TL
 - Pointing(?s – satellite, ?d - direction)
 - TurnTo(?s – satellite, ?ds – direction, ?de - direction)
 - instrument_TL
 - Calibrate(?s – satellite, ? d – direction, ?i - instrument)
 - TakeImage(?s – satellite, ? d – direction, ?i -instrument, ?m – mode)
 - power_TL
 - DivertedOnSat(?s – satellite, ?i - instrument)
 - DivertedOnInst(?s – satellite, ?i - instrument)
 - PowerInst(?i – instrument)
 - PowerSat(?s – satellite)
 - mode_TL
 - Support(?i -instrument, ?m – mode)

XIDDL: Domain

- Compatibilities

XIDDL: Objects (I)

```
<define_label_set>  
  <name>SatelliteValues</name>  
  <value>satelliteo</value>  
  <value>satelliteI</value>  
</define_label_set>
```

```
<define_label_set>  
  <name>InstrumentValues</name>  
  <value>instrumento</value>  
  <value>instrumentI</value>  
</define_label_set>
```

XIDDL: Objects (II)

```
<define_label_set>
  <name>DirectionValues</name>
  <value>GroundStation1</value>
  ...
  <value>Phenomenon6</value>
</define_label_set>
<define_label_set>
  <name>ModeValues</name>
  <value>image1</value>
  <value>spectrograph2</value>
  <value>thermographo</value>
</define_label_set>
```

XIDDL: Initial State

```
Object_Timelines SpaceOpDomain SpaceOpInstance  
(  
  SatelliteTL ([o] IdleSat() ...)  
  InstrumentTL ([o] IdleInst() ...)  
  PowerTL ([o] PowerSat ( satelliteo) ...)  
  ModeTL ([o] IdleMode() ...)  
)
```

XIDDL: IS & Goal

```
Object_Timelines SatelliteDomain SatelliteInstance (  
  SatelliteTL ([o] IdleSat() ...) ...  
  ModeTL ([o] IdleMode() ...))
```

```
Object_Timelines GoalClass GoalInstance (  
  GoalTL([o] IdleGoal() [io] TakeImageGoal(satelliteo instrumento  
  Phenomenon4 thermographo * *) [6o] ...))
```

```
Object_Timelines PlanningClass PlanningInstance (  
  PlanningSV ([o] IdlePlanning() [io] Planning() ... ))
```


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Conclusions

- Represent plan with soft constraints & goals
 - Best quality plan satisfy “as much as possible” the soft constraints & goals
- PDDL₂.X is extended: PDDL₃
- XIDDL based on NDDL (EUROPA planner)
 - Evolution of system along time
 - Basic structure TL