CS540 Introduction to Artificial Intelligence Lecture 18

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Uniformed vs. Informed Search

Motivation

- Uninformed search means only the goal G and the successor functions s' are given.
- Informed search means which non-goal states are better is also known.

Heuristic

Motivation

- The additional information is usually given as a heuristic cost from a state s to the goal.
- The cost of the path from the start to a vertex s in the frontier is $g(s)$.
- The cost from s to the goal, $h^\star(s)$, is estimated by $h(s)$. This estimate may not be accurate.

$$h(s) \approx h^\star(s)$$

Heuristic Diagram

Motivation

Uniform Cost Search

Description

- Expand the vertices with the lowest current path cost $g(s)$ first.
- It is BFS with a priority queue based on $g(s)$.
- It is equivalent to BFS if $c = 1$ is constant on all edges.
- It is also called Dijkstra's Algorithm.

Uniform Cost Search Maze Example

Definition

Uniform Cost Search Simple Example

Definition

Uniform Cost Search

Algorithm

- Input: a weighted digraph (V, E, c), initial states I and goal states G.
- Output: a path from I to G.
- EnQueue initial states into a priority queue Q. Here, Q is ordered by $g(s)$ for $s \in Q$.

$$Q = I$$

- While Q is not empty and goal is not deQueued, deQueue Q and enQueue its successors.

$$s = Q_{(0)} = \arg\min_{s \in Q} g(s)$$

$$Q = Q + s'(s)$$

Uniform Cost Search Performance

Discussion

- UCS is complete.
- UCS is optimal with any c.

Best First Greedy Search

Description

- Expand the vertices with the lowest heuristic cost $h(s)$ first.
- Use a priority queue based on $h(s)$.

Greedy Search Maze Example

Definition

Best First Greedy Search

Algorithm

- Input: a weighted digraph (V, E, c), initial states I and goal states G, and the heuristic function $h(s), s \in V$.
- Output: a path from I to G.
- EnQueue initial states into a priority queue Q. Here, Q is ordered by $h(s)$ for $s \in Q$.

$$Q = I$$

- While Q is not empty and goal is not deQueued, deQueue Q and enQueue its successors.

$$s = Q_{(0)} = \arg\min_{s \in Q} h(s)$$

$$Q = Q + s'(s)$$

Best First Greedy Search Performance

Discussion

- Greedy is incomplete.
- Greedy is not optimal.

A Search

Description

- Expand the vertices with the lowest total cost $g(s) + h(s)$ first.
- Use a priority queue based on $g(s) + h(s)$.
- A stands for Always be optimistic?

A Search Maze Example

Definition

A Search Simple Example 1

Definition

A Search Simple Example 2

Definition

A Search Simple Example 3

Definition

A Search

Algorithm

- Input: a weighted digraph (V, E, c), initial states I and goal states G, and the heuristic function $h(s), s \in V$.
- Output: a path from I to G.
- EnQueue initial states into a priority queue Q. Here, Q is ordered by $g(s) + h(s)$ for $s \in Q$.

$$Q = I$$

- While Q is not empty and goal is not deQueued, deQueue Q and enQueue its successors.

$$s = Q_{(0)} = \arg\min_{s \in Q} g(s) + h(s)$$

$$Q = Q + s'(s)$$

A Search Performance

Discussion

- A is complete.
- A is not optimal.

A Star Search

Description

- $A^{\star}$ search is A search with an admissible heuristic.

Admissible Heuristic

Definition

- A heuristic is admissible if it never over estimates the true cost.

$$0 \leqslant h(s) \leqslant h^{\star}(s)$$

Admissible Heuristic 8 Puzzle Example

Definition

Dominated Heuristic

Definition

- One heuristic, h_1, is dominated by another, h_2, if:

$$h_1(s) \leqslant h_2(s) \leqslant h^\star(s), \ \forall\ s \in S$$

- If h_2 dominates h_1, then h_2 is better than h_1 since $A^\star$ using h_1 expands at least as many states (or more) than $A^\star$ using $h_{2.}$
- If h_2 dominated $h_1, A^\star$ with h_2 is better informed than $A^\star$ with $h_{1.}$

Non-Optimal Heuristic

Definition

- If optimality is not required and a satisfying solution is acceptable, then the heuristic should be as close as possible, either under or over, to the actual cost.
- This results in fewer states being expanded compared to using poor but admissible heuristics.

A Star Search with Revisit, Part I

Algorithm

- Input: a weighted digraph (V, E, c), initial states I and goal states G, and the heuristic function $h(s), s \in V$.
- Output: a path with minimum cost from I to G.
- EnQueue initial states into a priority queue Q. Here, Q is ordered by $g(s) + h(s)$ for $s \in Q$.

$$Q = I$$
$$g(I) = 0$$
$$g(s) = \infty, \text{ for } s \notin I$$

- Initialize the list of visited vertices, P.

$$P = \emptyset$$

A Star Search with Revisit, Part II

Algorithm

- While Q is not empty and goal is not deQueued, deQueue Q, put it on P and enQueue its successors to Q, and update the cost functions.

$$s = Q_{(0)} = \arg\min_{s \in Q} g(s) + h(s)$$

$$P = P + s$$

$$Q = Q + s'(s), \text{ update } g(s') = \min\left\{g(s'), g(s) + c(s, s')\right\}$$

A Search Performance

Discussion

- $A^{\star}$ is complete.
- $A^{\star}$ is optimal.

Iterative Deepening A Star Search

Discussion

- $A^\star$ can use a lot of memory.
- Do path checking without expanding any vertex with $g(s) + h(s) > 1$.
- Do path checking without expanding any vertex with $g(s) + h(s) > 2$.
- ...
- Do path checking without expanding any vertex with $g(s) + h(s) > d$.

Iterative Deepening A Star Search Performance

Discussion

- IDA* is complete.
- IDA* is optimal.
- IDA* is more costly than $A^\star$.

Beam Search

Discussion

- Version 1: Keep a priority queue with fixed size k. Only keep the top k vertices and discard the rest.
- Version 2: Only keep the vertices that are at most ε worse than the best vertex in the queue. ε is called the beam width.

Beam Search Performance

Discussion

- Beam is incomplete.
- Beam is not optimal.