# Resolution

**Definition 1.** Consider a query

$$?\!-\ \phi_1, \ldots, \phi_n.$$

and a clause

$$\theta :\!-\ \psi_1, \ldots, \psi_m.$$

such that none of the variables in the clause appear in the query. Suppose that the $i$th formula $\phi_i$ can be unified with the head $\theta$ and let $\sigma$ be the most general unifier of $\phi_i$ and $\theta$.

We say that the query can be *resolved* against the clause and that the *resolvent* of the two is the query

$$?\!-\ \phi_1\sigma, \ldots, \phi_{i-1}\sigma,\ \psi_1\sigma, \ldots, \psi_m\sigma,\ \phi_{i+1}\sigma, \ldots \phi_n\sigma.$$

## Resolution proof

Prolog works backwards from the goal using resolution steps. The proof succeeds if eventually the query becomes empty.

Consider

```
?- likes(colin,Y).
```

The first step is to resolve the query against the clause

```
likes(X,Y):- cat(X), strokes(Y,X), feeds(Y,X).
```

but note that one of the variables in the clause appears in the query and resolution rules this out.

## Renaming variables

The strategy used in Prolog is to choose fresh names for the variables in a clause every time the clause is used.

Thus, we actually resolve against, say,

```
likes(X1,Y1):- cat(X1), strokes(Y1,X1), feeds(Y1,X1).
```

The renaming of variables becomes very important if the same clause is used twice in a proof.

The resolvent is

```
?- cat(colin), strokes(Y,colin), feeds(Y,colin).
```

The first subgoal resolves immediatedly against a unit clause to give

```
?- strokes(Y,colin), feeds(Y,colin).
```

We can resolve against the clause

```
strokes(Y2,X2):- cat(X2), human(Y2), likes(Y2,X2).
```

to obtain

```
?- cat(colin), human(Y), likes(Y,colin), feeds(Y,colin).
```

The subgoals now can be resolved one-by-one against unit clauses leaving the empty query $\Box$ and we are done.

## SLD-Resolution

To organize an automatic search for a proof, one must choose:

1. (a) at each step, the subgoal to be considered,
   (b) the program clause to resolve it with;
2. the overall strategy to be used.

The execution of Prolog programs is based on the scheme:

1. (a) select the first subgoal in the list,
   (b) resolve with the program clauses in the order they are listed;
2. use a depth-first search strategy (we'll see this shortly).

This scheme is known as *SLD-resolution* which is short for "Selection driven Linear resolution for Definite clauses".

**Example 2.** Consider the program

```
parent(g,a).
parent(g,r).
parent(r,s).
parent(r,j).

grandparent(X,Y):- parent(X,Z), parent(Z,Y).

before(X,Y):- parent(Z,X), grandparent(Z,Y).
```

The predicate `before` expresses the relation that one person is in the generation before another.

# SLD-trees

One can picture the search for a proof as a tree of possibilities.

$?\!-\ before(a, Y).$

$?\!-\ parent(Z_1, a), grandparent(Z_1, Y).$

$Z_1 = g$

$?\!-\ grandparent(g, Y).$

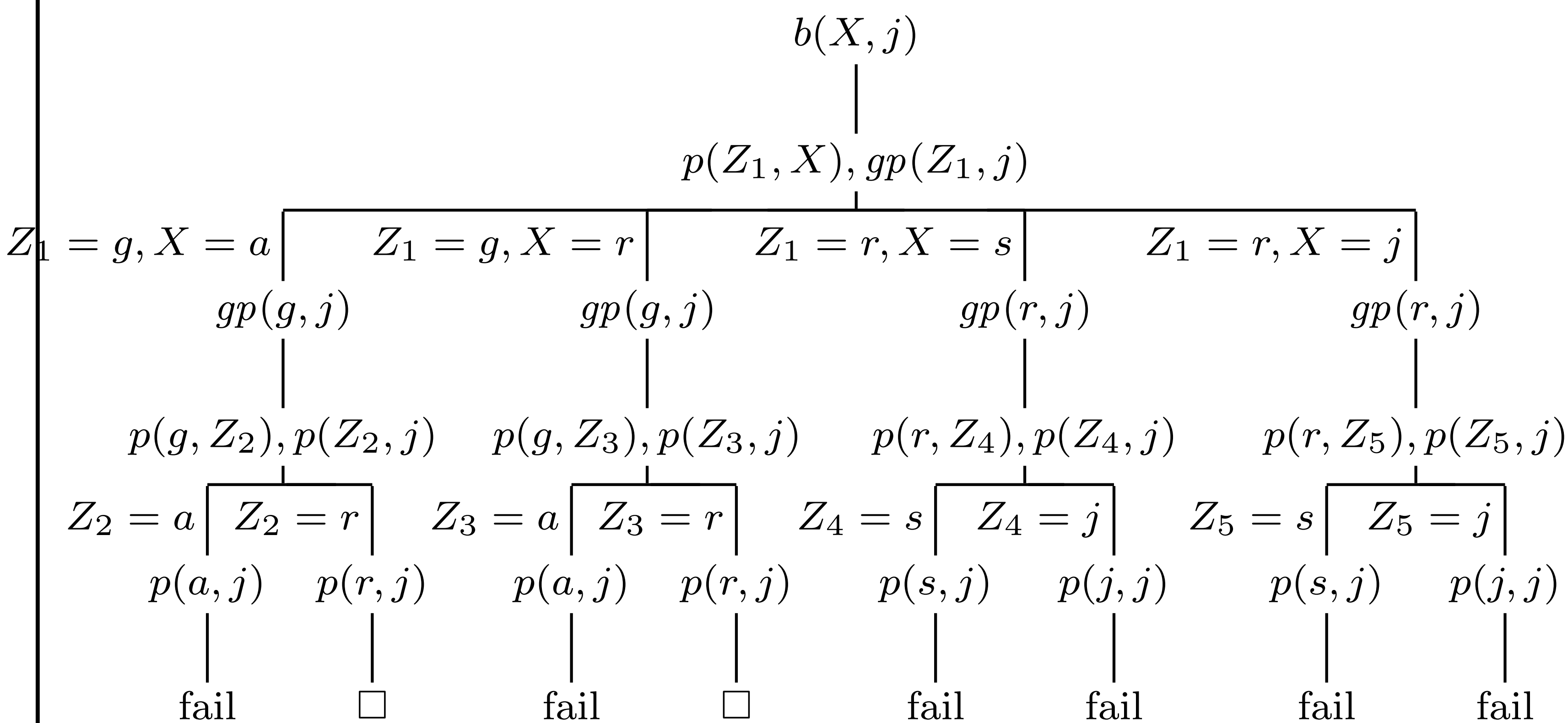
$?\!-\ parent(g, Z_2), parent(Z_2, Y).$

$Z_2 = a$ $\qquad$ $Z_2 = r$

$?\!-\ parent(a, Y).$ $\qquad$ $?\!-\ parent(r, Y).$

$Y = s$ $\qquad$ $Y = j$

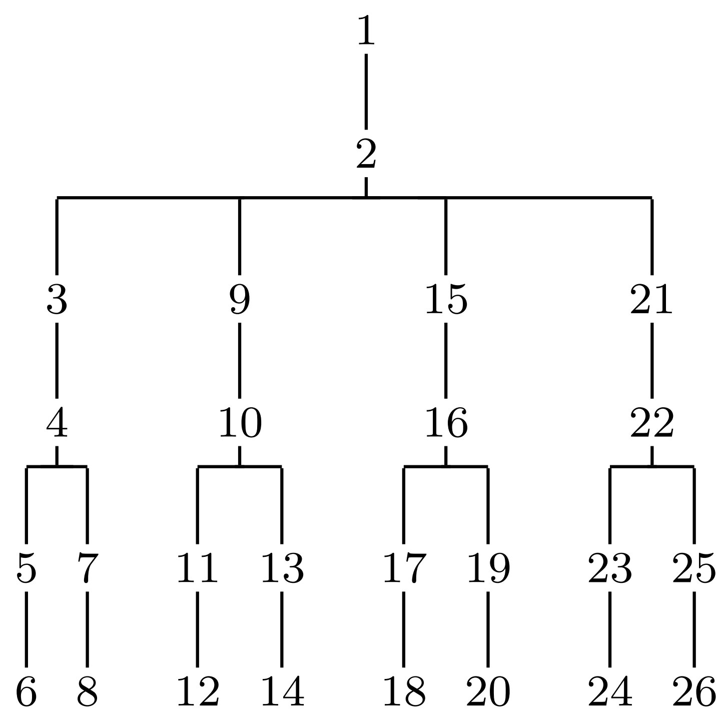
fail $\qquad$ $\square$ $\qquad$ $\square$



$b(X,j)$
$p(Z_1,X), gp(Z_1,j)$
$Z_1 = g, X = a$
$Z_1 = g, X = r$
$Z_1 = r, X = s$
$Z_1 = r, X = j$
$gp(g,j)$
$gp(g,j)$
$gp(r,j)$
$gp(r,j)$
$p(g,Z_2), p(Z_2,j)$
$p(g,Z_3), p(Z_3,j)$
$p(r,Z_4), p(Z_4,j)$
$p(r,Z_5), p(Z_5,j)$
$Z_2 = a$
$Z_2 = r$
$Z_3 = a$
$Z_3 = r$
$Z_4 = s$
$Z_4 = j$
$Z_5 = s$
$Z_5 = j$
$p(a,j)$
$p(r,j)$
$p(a,j)$
$p(r,j)$
$p(s,j)$
$p(j,j)$
$p(s,j)$
$p(j,j)$
fail
$\Box$
fail
$\Box$
fail
fail
fail
fail

# Depth-first search

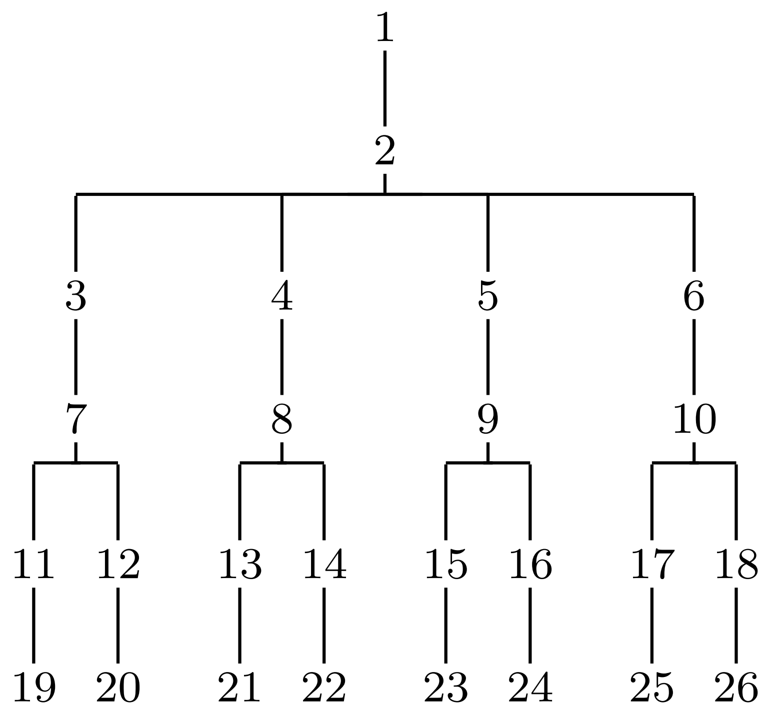
Fully explore each subtree to the left before moving on to the next subtree to the right. The nodes are traversed in the order below.




This is easy to implement without using too much memory.

## Breadth-first search

Explore each successive level of the tree before looking at the next level down.




This requires far more memory than a depth-first search but it is nevertheless sometimes appropriate.