

# COMP90054 – Week 5 tutorial

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## Generating heuristic function via relaxation

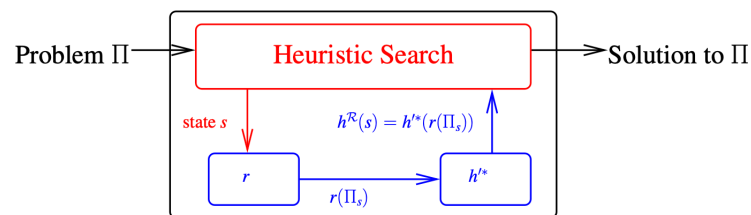
### Objective

- Find an estimate of the perfect heuristic  $h^*$  for problem  $\mathcal{P}$

### Relaxation

- Relaxation is a method to compute heuristic functions
- Steps
  - Simplifying the original problem  $\mathcal{P}$  to a relaxed problem  $\mathcal{P}'$
  - $\mathcal{P}'$  has perfect heuristic  $h'^*$  which can be used to admissibly estimate  $h^*$
  - Define a transformation  $r$  that simplify  $\mathcal{P}$  to  $\mathcal{P}'$
  - Given a specific planning task  $\Pi \in \mathcal{P}$ , estimate  $h^*(\Pi)$  by  $h'^*(r(\Pi))$
- Relaxation can be native, efficiently constructible ( $r(\Pi)$ ), and/or efficiently computable ( $h'^*(\Pi')$ )
  - if  $r$  or  $h'^*$  cannot be efficiently computed, we may choose to approximate them, design them so that they are feasible in most cases, or just use brute force 😊

Using a relaxation  $\mathcal{R} = (\mathcal{P}', r, h'^*)$  during search:



→  $\Pi_s$ :  $\Pi$  with initial state replaced by  $s$ , i.e.,  $\Pi = (F, A, c, I, G)$  changed to  $(F, A, c, s, G)$ .

### Example

- Problem:** Grid world (move up/down/left/right, can't move through walls)
- Simplified problem  $\mathcal{P}'$ :** Grid world but can move through walls
- Transformation  $r$ :** Remove preconditions of checking wall at target cell
- Optimal Heuristic for  $\mathcal{P}'$   $h'^*$ :** Manhattan distance from current position to goal

## PDDL

## Propositional Domain Definition Language

- Components of a PDDL planning task
  - Objects: Things in the world we defined
  - Predicates: Properties of the objects, can be true or false
  - Initial state: The state of the world that we start in
  - Goal specification: Things that we want to be true
  - Actions/Operators: Ways of changing the state of the world
- An implementation of PDDL planning task consists of two files
  - Domain file: defines the predicates and operators
  - Problem file: defines the objects, the initial state and the goal state
- Tips
  - *predicate(x, y)* does not imply *predicate(y, x)*
  - `:typing` can be useful if have multiple types of objects, so PDDL only search the relevant type of variables during search

## TSP Example

- Let  $C$  be the set of cities,  $E$  be the set of directed edges showing connected cities
- $P = \langle F, O, I, G \rangle$ 
  - $F = \{at(x), visited(x), connected(x, y) \mid x \in C, (x, y) \in E\}$
  - $I = \{at(sydney), visited(sydney), connected(x, y) \mid (x, y) \in E\}$
  - $G = \{visited(x) \mid x \in C\}$
  - $O = \left\{ move(x, y) \left\{ \begin{array}{l} pre: at(x), connected(x, y) \\ add: at(y), visited(y) \mid (x, y) \in E \\ del: at(x) \end{array} \right. \right\}$

## • Domain

```
;; TSP PDDL ***Domain File***

(define (domain tsp)
  (:requirements :typing)
  (:types node)

  ;; Define the facts in the problem
  ;; "?" denotes a variable, "-" a type
  (:predicates
    (at ?pos - node)
    (connected ?start ?end - node)
    (visited ?end - node)
  )

  ;; Define the action(s)
  (:action move
    :parameters (?start ?end - node)
    :precondition (and
      (at ?start)
      (connected ?start ?end)
    )
    :effect (and
      (at ?end)
      (visited ?end)
      (not (at ?start))
    )
  )
)
```

- Problem

```
;; TSP PDDL ***Problem File***

(define (problem tsp-01)
  (:domain tsp)
  (:objects Sydney Adelaide Brisbane Perth Darwin - node)

  ;; Define the initial situation
  (:init (connected Sydney Brisbane)
         (connected Brisbane Sydney)
         (connected Adelaide Sydney)
         (connected Sydney Adelaide)
         (connected Adelaide Perth)
         (connected Perth Adelaide)
         (connected Adelaide Darwin)
         (connected Darwin Adelaide)
         (at Sydney)
  )
  (:goal
    (and
      (at Sydney)
      (visited Sydney)
      (visited Adelaide)
      (visited Brisbane)
      (visited Perth)
      (visited Darwin)
    )
  )
)
```