CST401
ARTIFICIAL INTELLIGENCE

MODULE 3

SYLLABUS- Problem Solving

- Adversarial search - Games,
- Optimal decisions in games,
- The Minimax algorithm,
- Alpha-Beta pruning.
- Constraint Satisfaction Problems – Defining CSP,
- Constraint Propagation- inference in CSPs,
- Backtracking search for CSPs,
- Structure of CSP problems.

ADVERSARIAL SEARCH

In which we examine the problems that arise when we try to plan ahead in a world

where other agents are planning against us.

GAMES

competitive environments, in which the agent's goals are in conflict

Games are easy to formalize

Games can be a good model of real-world competitive or cooperative activities

Military confrontations, negotiation, auctions, etc.

	Deterministic	**Stochastic**
Perfect information (fully observable)	Chess, checkers, go	Backgammon, monopoly
Imperfect information (partially observable)	Battleships	Scrabble, poker, bridge

Alternating two-player zero-sum games

Players take turns

Each game outcome or terminal state has a utility for each player (e.g., 1 for win, 0 for loss)

The sum of both players' utilities is a constant

Games vs. single-agent search

We don't know how the opponent will act

- The solution is not a fixed sequence of actions from start state to goal state, but a strategy or policy (a mapping from state to best move in that state)

Efficiency is critical to playing well

- The time to make a move is limited
- The branching factor, search depth, and number of terminal configurations are huge
  - In chess, branching factor ≈ 35 and depth ≈ 100, giving a search tree of nodes
    - Number of atoms in the observable universe ≈ 1080
  - This rules out searching all the way to the end of the game

PRUNING

optimal move and an algorithm for finding it

choosing a good move when time is limited

Pruning allows us to ignore portions of the search tree that make no difference to the final choice, and

heuristic **evaluation functions** allow us to approximate the true utility of a state without doing a complete search

MIN- MAX

MAX moves first, and then they take turns moving until the game is over.

At the end of the game, points are awarded to the winning player and penalties are given to the loser.

A game can be formally defined as a kind of search problem with the following elements:

- S_0: The **initial state**, which specifies how the game is set up at the start.
- PLAYER(s): Defines which player has the move in a state.
- ACTIONS(s): Returns the set of legal moves in a state.
- RESULT(s, a): The **transition model**, which defines the result of a move.
- TERMINAL-TEST(s): A **terminal test**, which is true when the game is over and false otherwise. States where the game has ended are called **terminal states**.
- UTILITY(s, p): A **utility function** (also called an objective function or payoff function), defines the final numeric value for a game that ends in terminal state s for a player p. In chess, the outcome is a win, loss, or draw, with values $+1$, 0, or $\frac{1}{2}$. Some games have a wider variety of possible outcomes; the payoffs in backgammon range from 0 to $+192$. A **zero-sum game** is (confusingly) defined as one where the total payoff to all players is the same for every instance of the game. Chess is zero-sum because every game has payoff of either $0 + 1$, $1 + 0$ or $\frac{1}{2} + \frac{1}{2}$. "Constant-sum" would have been a better term, but zero-sum is traditional and makes sense if you imagine each player is charged an entry fee of $\frac{1}{2}$.

Game tree

The initial state, ACTIONS function, and RESULT function define the **game tree** for the game a tree where the nodes are game states and the edges are moves.
From the initial state, MAX has nine possible moves.
Play alternates between MAX's placing an X and MIN's placing an O until we reach leaf nodes corresponding to terminal states such that one player has three in a row or all the squares are filled
The number on each leaf node indicates the utility value of the terminal state from the point of view of MAX;
high values are assumed to be good for MAX and bad for MIN

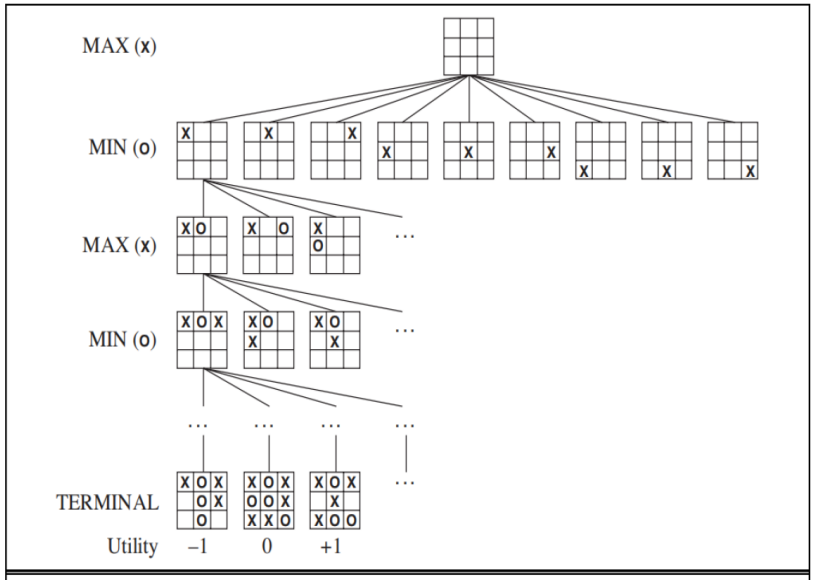


Figure 5.1 A (partial) game tree for the game of tic-tac-toe. The top node is the initial state, and MAX moves first, placing an X in an empty square. We show part of the tree, giving alternating moves by MIN (O) and MAX (X), until we eventually reach terminal states, which can be assigned utilities according to the rules of the game.

search tree *is a tree that is superimposed on the full game tree, and examines enough nodes to allow a player to determine what move to make.*

OPTIMAL DECISIONS IN GAMES

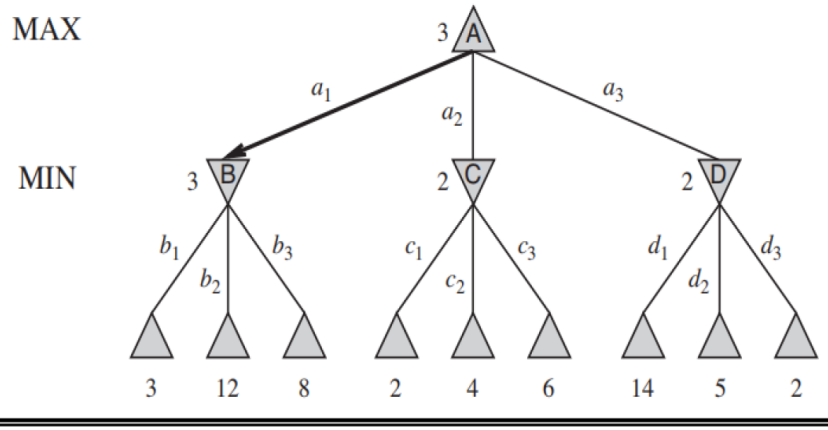


Figure 5.2 A two-ply game tree. The △ nodes are "MAX nodes," in which it is MAX's turn to move, and the ▽ nodes are "MIN nodes." The terminal nodes show the utility values for MAX; the other nodes are labeled with their minimax values. MAX's best move at the root is a_1, because it leads to the state with the highest minimax value, and MIN's best reply is b_1, because it leads to the state with the lowest minimax value.

Minimax Value and Minimax Decision

The minimax value of a node is of being useful in the corresponding state, *assuming that both players play optimally* from there to the end of the game.

the minimax value of a terminal state is just its utility(the state of being useful).

MAX prefers to move to a state of maximum value, whereas MIN prefers a state of minimum value.

The terminal nodes on the bottom level get their utility values from the game's UTILITY function

minimax decision: optimal choice for MAX at root that leads to the state with the highest minimax value

$$\textsc{Minimax}(s) = \begin{cases} \textsc{Utility}(s) & \text{if } \textsc{Terminal-Test}(s) \\ \max_{a \in Actions(s)} \textsc{Minimax}(\textsc{Result}(s,a)) & \text{if } \textsc{Player}(s) = \textsc{max} \\ \min_{a \in Actions(s)} \textsc{Minimax}(\textsc{Result}(s,a)) & \text{if } \textsc{Player}(s) = \textsc{min} \end{cases}$$

The minimax algorithm

minimax algorithm computes the minimax decision from the current state.

The recursion proceeds all the way down to the leaves of the tree, and then the minimax values are **backed up** through the tree as the recursion unwinds.

minimax algorithm performs a complete depth-first exploration of the game tree

```
function MINIMAX-DECISION(state) returns an action
  return arg max_{a ∈ ACTIONS(s)} MIN-VALUE(RESULT(state, a))

function MAX-VALUE(state) returns a utility value
  if TERMINAL-TEST(state) then return UTILITY(state)
  v ← −∞
  for each a in ACTIONS(state) do
    v ← MAX(v, MIN-VALUE(RESULT(s, a)))
  return v

function MIN-VALUE(state) returns a utility value
  if TERMINAL-TEST(state) then return UTILITY(state)
  v ← ∞
  for each a in ACTIONS(state) do
    v ← MIN(v, MAX-VALUE(RESULT(s, a)))
  return v
```

Figure 5.3 An algorithm for calculating minimax decisions. It returns the action corresponding to the best possible move, that is, the move that leads to the outcome with the best utility, under the assumption that the opponent plays to minimize utility. The functions MAX-VALUE and MIN-VALUE go through the whole game tree, all the way to the leaves, to determine the backed-up value of a state. The notation $\text{argmax}_{a \in S} f(a)$ computes the element a of set S that has the maximum value of $f(a)$.

maximum depth of the tree is m and there are b legal moves at each point,

time complexity →O(b m).

space complexity → O(bm), for an algorithm that generates all actions at once,

or O(m), for an algorithm that generates actions one at a time

Optimal decisions in multiplayer games

replace the single value for each node with a *vector* of values

in a three-player game with players A, B, and C, a vector vA, vB, vC is associated with each node

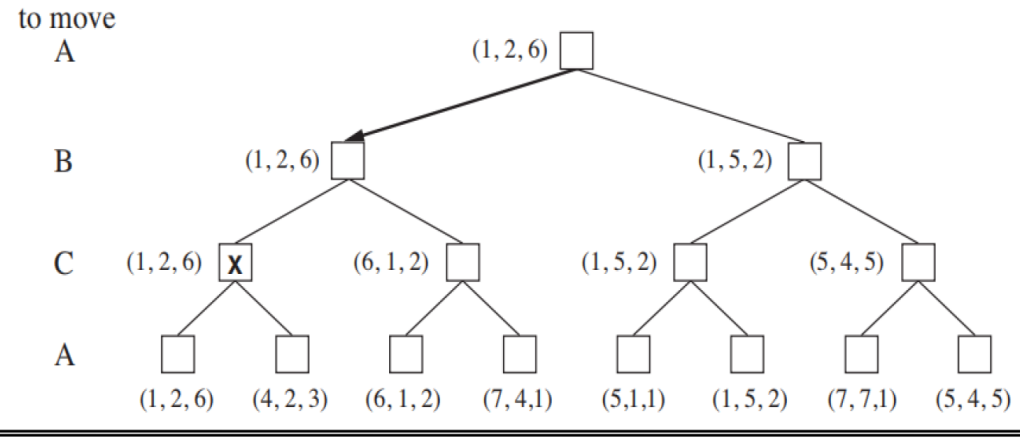


Figure 5.4 The first three plies of a game tree with three players (A, B, C). Each node is labeled with values from the viewpoint of each player. The best move is marked at the root.

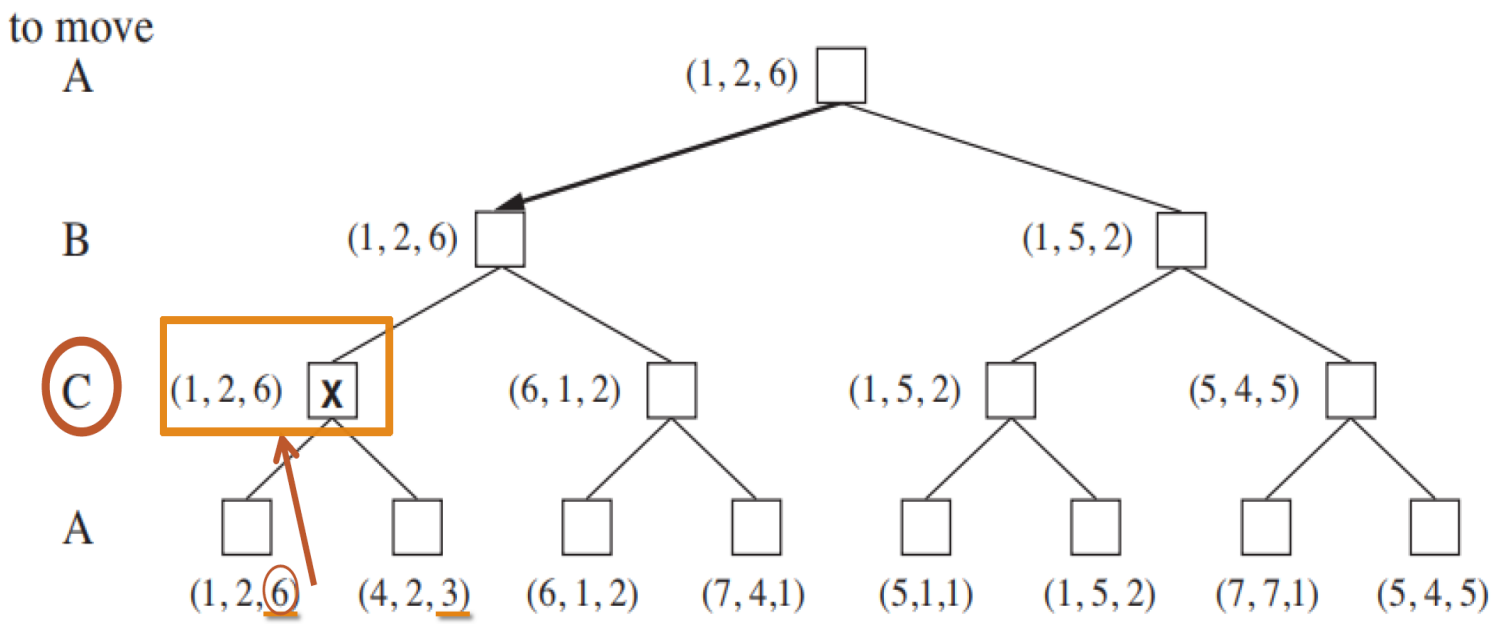


Figure 5.4 The first three plies of a game tree with three players (A, B, C). Each node is labeled with values from the viewpoint of each player. The best move is marked at the root.

The backed-up value of a node n is always the utility vector of the successor state with the highest value for the player choosing at n

ALPHA BETA PRUNING

The problem with minimax search is that the number of game states it has to examine is exponential in the depth of the tree

To avoid this it is possible to compute the correct minimax decision without looking at every node in the game tree by **pruning**

In alpha beta pruning algorithm it prunes away branches that cannot possibly influence the final decision

Alpha–beta pruning can be applied to trees of any depth, and it is often possible to prune entire subtrees rather than just leaves

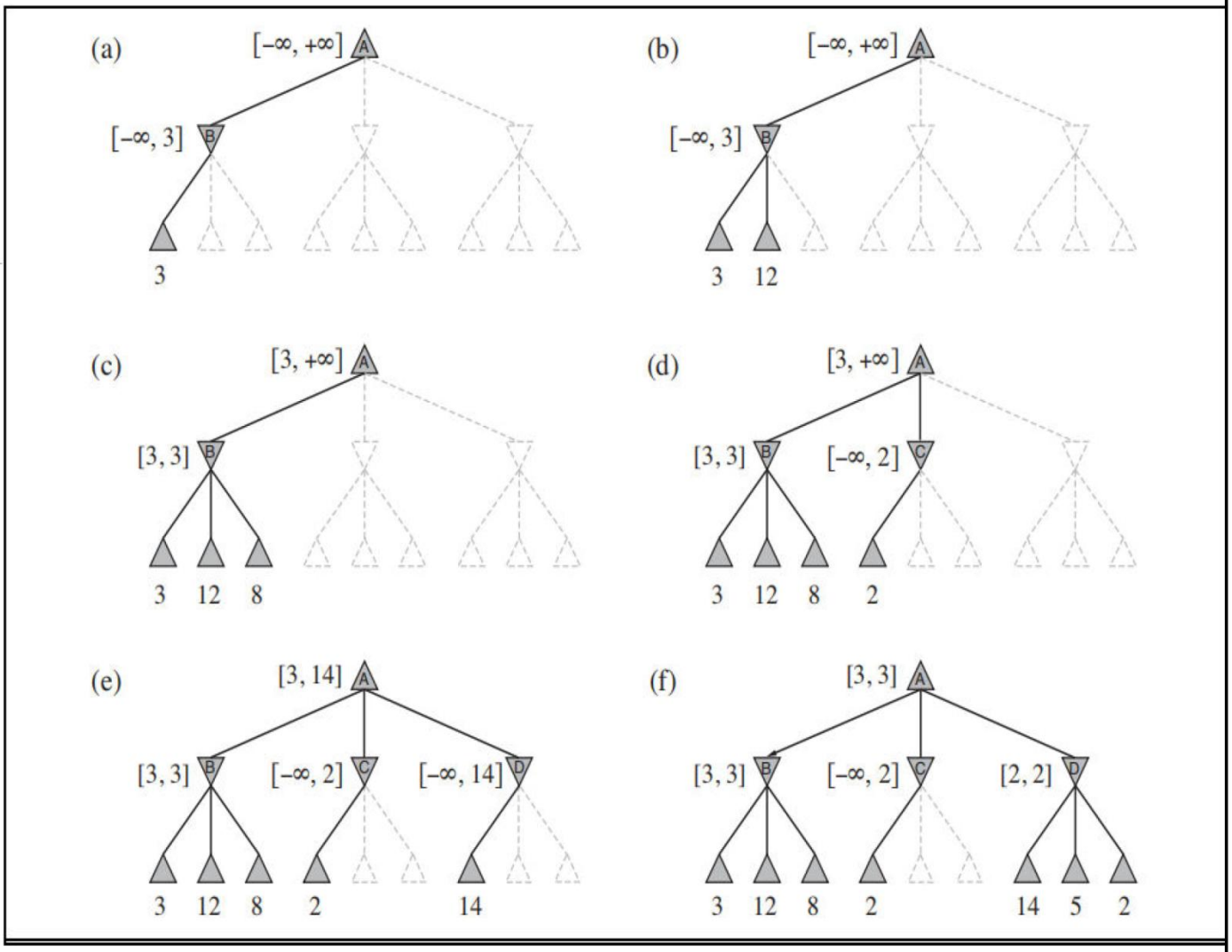
If Player has a better choice m either at the parent node of n or at any choice point further up, then n *will never be reached in actual play.* So once we have found out enough about n (by examining some of its descendants) to reach this conclusion, we can prune it.

$\alpha =$ the value of the best (i.e., highest-value) choice we have found so far at any choice point along the path for MAX.

$\beta =$ the value of the best (i.e., lowest-value) choice we have found so far at any choice point along the path for MIN.

Alpha–beta search updates the values of α and β as it goes along and prunes the remaining branches at a node (i.e., terminates the recursive call) as soon as the value of the current node is known to be worse than the current α or β value for MAX or MIN, respectively

The outcome is that we can identify the minimax decision without ever evaluating two of the leaf nodes.



Let the two unevaluated successors of node C have values x and y Then the value of the root node is given by

$$\begin{aligned}
\textsc{Minimax}(root) &= \max(\min(3,12,8), \min(2,x,y), \min(14,5,2)) \\
&= \max(3, \min(2,x,y), 2) \\
&= \max(3,z,2) \qquad \text{where } z = \min(2,x,y) \leq 2 \\
&= 3.
\end{aligned}$$

In other words, the value of the root and hence the minimax decision are independent of the values of the pruned leaves x and y.

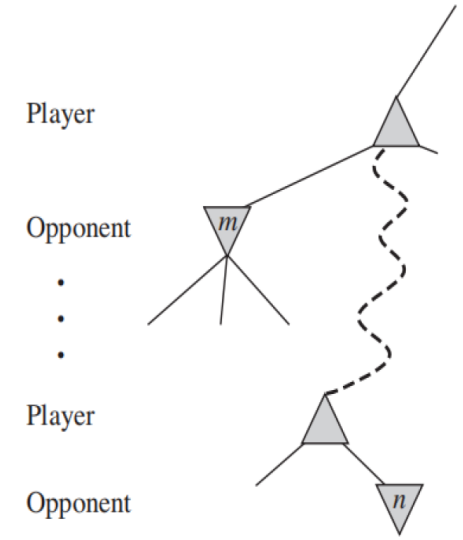


Figure 5.6 The general case for alpha–beta pruning. If m is better than n for Player, we will never get to n in play.

```
function ALPHA-BETA-SEARCH(state) returns an action
  v ← MAX-VALUE(state, −∞, +∞)
  return the action in ACTIONS(state) with value v

function MAX-VALUE(state, α, β) returns a utility value
  if TERMINAL-TEST(state) then return UTILITY(state)
  v ← −∞
  for each a in ACTIONS(state) do
    v ← MAX(v, MIN-VALUE(RESULT(s,a), α, β))
    if v ≥ β then return v
    α ← MAX(α, v)
  return v

function MIN-VALUE(state, α, β) returns a utility value
  if TERMINAL-TEST(state) then return UTILITY(state)
  v ← +∞
  for each a in ACTIONS(state) do
    v ← MIN(v, MAX-VALUE(RESULT(s,a) , α, β))
    if v ≤ α then return v
    β ← MIN(β, v)
  return v
```

Figure 5.7 The alpha–beta search algorithm. Notice that these routines are the same as the MINIMAX functions in Figure 5.3, except for the two lines in each of MIN-VALUE and MAX-VALUE that maintain α and β (and the bookkeeping to pass these parameters along).

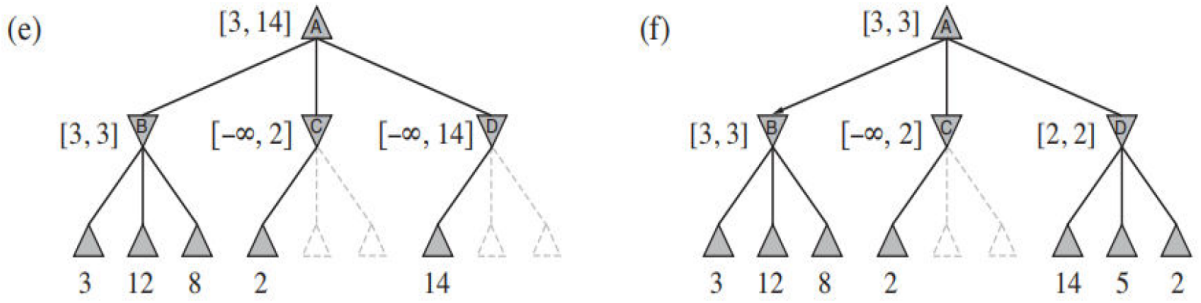
Move ordering

The effectiveness of alpha–beta pruning is highly dependent on the order in which the states are examined

Eg, here we could not prune any successors of D at all because the worst successors (from the point of view of MIN) were generated first

If the third successor of D had been generated first, we would have been able to prune the other two.

it might be worthwhile to try to examine first the successors that are likely to be best



Constraint Satisfaction Problem

CSP PROBLEM IS SOLVED WHEN EACH VARIABLE HAS A VALUE THAT SATISFIES ALL THE CONSTRAINTS ON THE VARIABLE

DEFINING CONSTRAINT SATISFACTION PROBLEMS

A constraint satisfaction problem consists of three components, X, D, and C:

- X is a set of variables, {X1,...,Xn}.
- D is a set of domains, {D1,...,Dn}, one for each variable.
- C is a set of constraints that specify allowable combinations of values.

Each domain Di consists of a set of allowable values, {v1,...,vk} for variable Xi.

Each constraint Ci consists of a pair scope, rel , where scope is a tuple of variables that participate in the constraint and rel is a relation that defines the values that those variables can take on.

A relation can be represented as an explicit list of all tuples of values that satisfy the constraint

an abstract relation that supports two operations:

- testing if a tuple is a member of the relation and
- enumerating the members of the relation.

For example, if X1 and X2 both have the domain {A,B}, then the constraint saying the two variables must have different values can be written as $\langle (X_1, X_2), [(A, B), (B, A)] \rangle$ or as $\langle (X_1, X_2), X_1 \neq X_2 \rangle$

Solving a CSP

To solve a CSP we need to define a state space and the notion of a solution

Each state in a CSP is defined by an **assignment** of values to some or all of the variables, {Xi = vi, Xj = vj ,...}.

An assignment that does not violate any constraints is called a **consistent** or legal assignment.

A **complete assignment** is one in which every variable is assigned, and

a **solution** to a CSP is a consistent, complete assignment

A **partial assignment** is one that assigns values to only some of the variables.

Example problem: Map coloring

We are given the task of coloring each region either red, green, or blue in such a way that no neighboring regions have the same color.

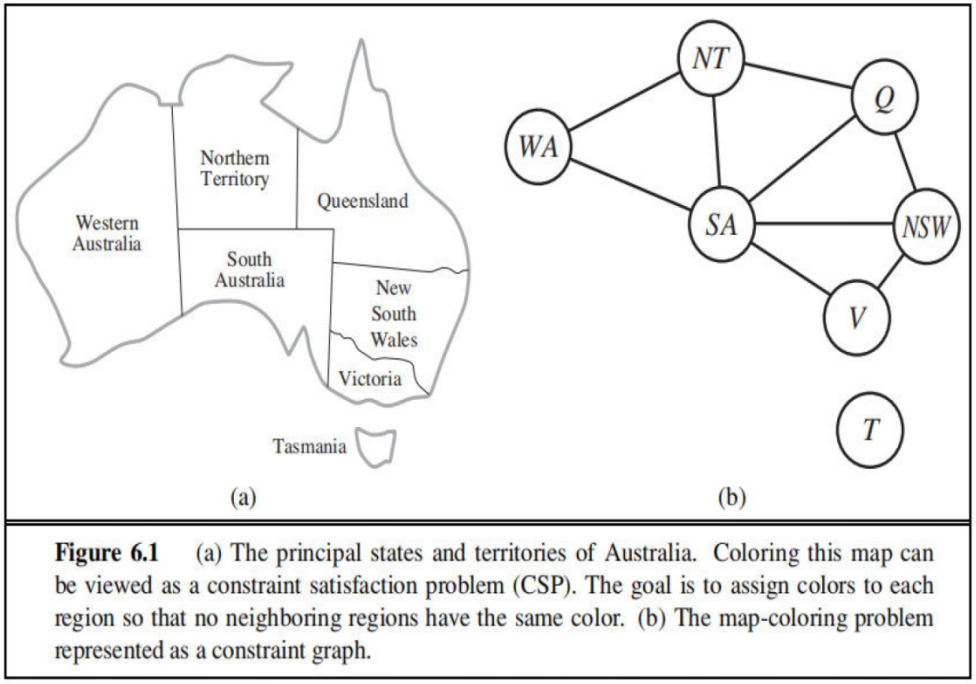


Figure 6.1 (a) The principal states and territories of Australia. Coloring this map can be viewed as a constraint satisfaction problem (CSP). The goal is to assign colors to each region so that no neighboring regions have the same color. (b) The map-coloring problem represented as a constraint graph.

X = {WA, NT, Q, NSW ,V, SA, T}

The domain of each variable is the set Di = {red, green, blue}.

The constraints require neighboring regions to have distinct colors. Since there are nine places where regions border, there are nine constraints:\

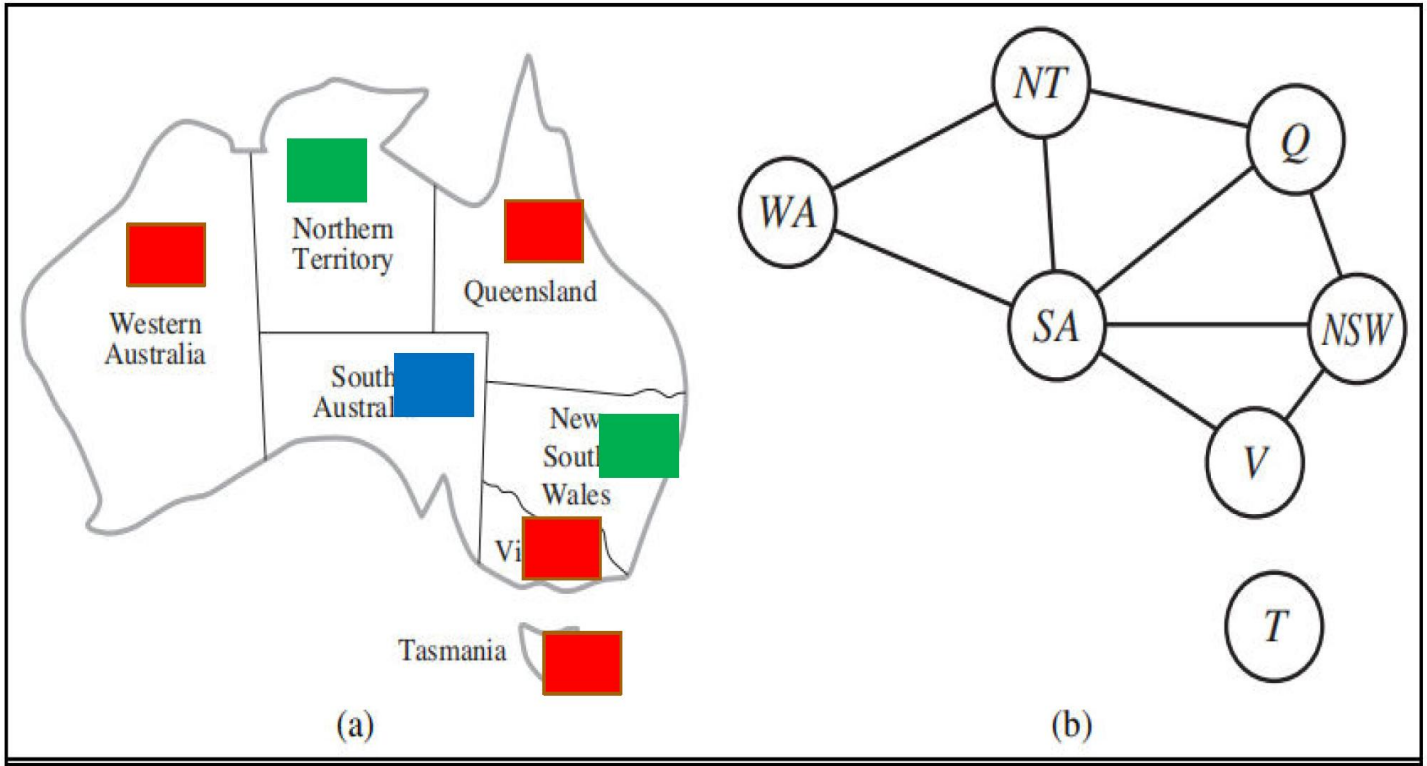
$$C = \{SA \neq WA, SA \neq NT, SA \neq Q, SA \neq NSW, SA \neq V, \\ WA \neq NT, NT \neq Q, Q \neq NSW, NSW \neq V\} .$$

Here we are using abbreviations; $SA \neq WA$ is a shortcut for $\langle (SA, WA), SA \neq WA \rangle$, where $SA \neq WA$ can be fully enumerated in turn as

$$\{(red, green), (red, blue), (green, red), (green, blue), (blue, red), (blue, green)\} .$$

There are many possible solutions to this problem, such as

$$\{ WA = red, NT = green, Q = red, NSW = green, V = red, SA = blue, T = red \}.$$



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Why formulate a problem as a CSP

CSPs yield a natural representation for a wide variety of problems: it is easier to solve a problem using CSP problem solver than to design a custom solution using another search technique

CSP solvers can be faster than state-space searchers because the CSP solver can quickly eliminate large swatches of the search space

- Eg, once we have chosen {SA = blue} in the Australia problem, we can conclude that none of the five neighboring variables can take on the value blue.

Without taking advantage of constraint propagation, a search procedure would have to consider $3^5 = 243$ assignments for the five neighboring variables;

with constraint propagation we never have to consider blue as a value, so we have only $2^5 = 32$ assignments to look at, a reduction of 87%.

Once we find out that a partial assignment is not a solution, we can immediately discard further refinements of the partial assignment.

Furthermore, we can see *why* the assignment is not a solution we see which variables violate a constraint—so we can focus attention on the variables that matter.

As a result, many problems that are intractable for regular state-space search can be solved quickly when formulated as a CSP.

Example problem: Job-shop scheduling

Factories have the problem of scheduling a day's worth of jobs, subject to various constraints.

Consider the problem of scheduling the assembly of a car.

The whole job is composed of tasks, and we can model each task as a variable, where the value of each variable is the time that the task starts, expressed as an integer number of minutes.

Constraints can assert that one task must occur before another

- a wheel must be installed before the hubcap is put on and
- that only so many tasks can go on at once.
- a task takes a certain amount of time to complete

Precedence constraints

Whenever a task T1 must occur before task T2, and task T1 takes duration d1 to complete, we add an arithmetic constraint of the form

$T1 + d1 \leq T2$

a small part of the car assembly, consisting of 15 tasks: install axles (front and back), affix all four wheels (right and left, front and back), tighten nuts for each wheel, affifix hubcaps, and inspect the fifinal assembly. We can represent the tasks with 15 variables:

X = {AxleF , AxleB,Wheel RF ,Wheel LF ,WheelRB,Wheel LB, NutsRF , NutsLF , NutsRB, NutsLB, CapRF , CapLF , CapRB, CapLB,Inspect} .

The value of each variable is the time that the task starts.

In our example, the axles have to be in place before the wheels are put on, and it takes 10 minutes to install an axle, so we write

$$Axle_F + 10 \leq Wheel_{RF}; \quad Axle_F + 10 \leq Wheel_{LF};$$
$$Axle_B + 10 \leq Wheel_{RB}; \quad Axle_B + 10 \leq Wheel_{LB} .$$

Next we say that, for each wheel, we must affix the wheel (which takes 1 minute), then tighten the nuts (2 minutes), and finally attach the hubcap (1 minute, but not represented yet):

$$Wheel_{RF} + 1 \leq Nuts_{RF}; \quad Nuts_{RF} + 2 \leq Cap_{RF};$$
$$Wheel_{LF} + 1 \leq Nuts_{LF}; \quad Nuts_{LF} + 2 \leq Cap_{LF};$$
$$Wheel_{RB} + 1 \leq Nuts_{RB}; \quad Nuts_{RB} + 2 \leq Cap_{RB};$$
$$Wheel_{LB} + 1 \leq Nuts_{LB}; \quad Nuts_{LB} + 2 \leq Cap_{LB} .$$

DISJUNCTIVE CONSTRAINT

Suppose we have four workers to install wheels, but they have to share one tool that helps put the axle in place.

We need a **disjunctive constraint** to say that AxleF and AxleB must not overlap in time; either one comes first or the other does:

$$(\text{AxleF} + 10 \leq \text{AxleB}) \textbf{ or}$$

$$(\text{AxleB} + 10 \leq \text{AxleF})$$

For every variable except Inspect we add a constraint of the form X + dX ≤ Inspect.

Finally, suppose there is a requirement to get the whole assembly done in 30 minutes.

- We can achieve that by limiting the domain of all variables: Di = {1, 2, 3,..., 27} .

This particular problem is trivial to solve, but CSPs have been applied to job-shop scheduling problems like this with thousands of variables.

Variations on the CSP formalism

Discrete variables

- Finite domains – Map coloring, scheduling with time limit, 8-queens problem
- Infinite domains- no deadline job-scheduling problem,
  - Linear constraints solvable, non-linear constraints are undecidable
  - no algorithm exists for solving general **nonlinear constraints** on integer variables

Continuous variables- eg scheduling of experiments on the Hubble Space Telescope requires very precise timing of observations;

- **linear programming** problems- where constraints must be linear equalities or inequalities
- Linear programming problems can be solved in time polynomial in the number of variables

Types of constraints

unary constraint- which restricts the value of a single variable

- Eg, map-coloring problem it could be the case that South Australians won't tolerate the color green; we can express that with the $\langle (SA), SA \neq green \rangle$

binary constraint- relates two variables

- A binary CSP is one with only binary constraints; it can be represented as a constraint graph

$SA \neq NSW$

We can also describe higher-order constraints, such as asserting that the value of Y is between X and Z, with the ternary constraint Between(X, Y, Z).

global constraint- A constraint involving an arbitrary number of variables

- Eg, In Sudoku problems all variables in a row or column must satisfy an Alldiffff , which says that all of the variables involved in the constraint must have different values

Real World CSP Problems

Teaching assignments

Timetabling

Hardware configuration (VLSI layout)

Logistics (transport scheduling)

Job shop scheduling (Operations research)

Cryptarithmetic puzzles

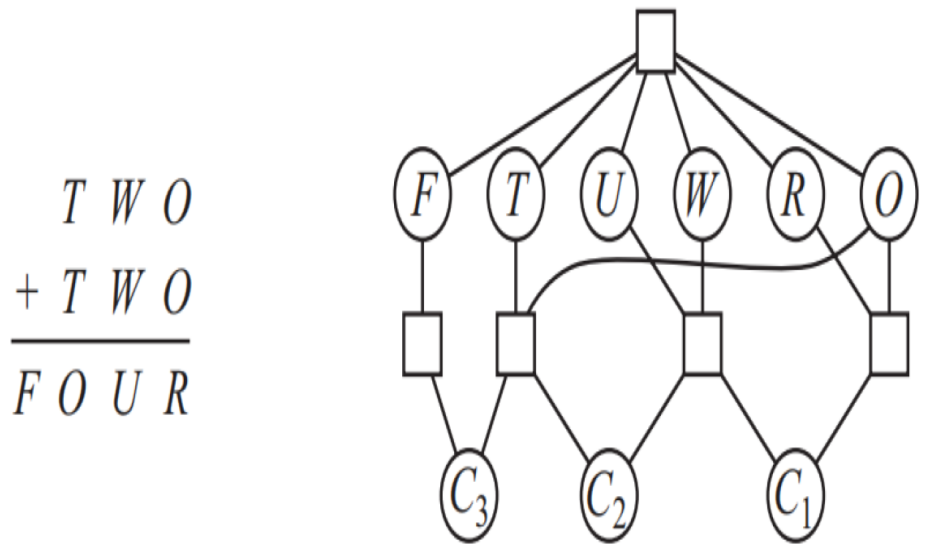


Figure 6.2 (a) A cryptarithmetic problem. Each letter stands for a distinct digit; the aim is to find a substitution of digits for letters such that the resulting sum is arithmetically correct, with the added restriction that no leading zeroes are allowed. (b) The constraint hypergraph for the cryptarithmetic problem, showing the *Alldiff* constraint (square box at the top) as well as the column addition constraints (four square boxes in the middle). The variables C_1, C_2, and C_3 represent the carry digits for the three columns.

Each letter in a cryptarithmetic puzzle represents a different digit

global constraint ➔ Alldifff. (F, T, U, W, R, O)

addition constraints on the four columns of the puzzle can be written as the following n-ary constraints:

$O + O = R + 10 \cdot C10$

$C10 + W + W = U + 10 \cdot C100$

$C100 + T + T = O + 10 \cdot C1000$

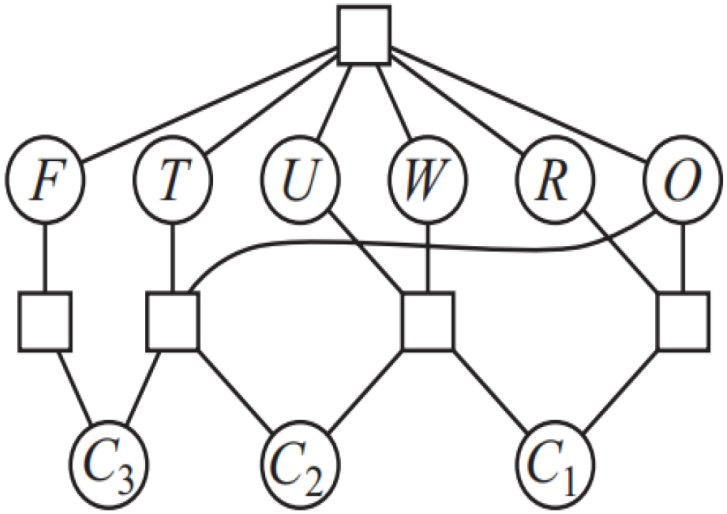
$C1000 = F$,

where C10, C100, and C1000 are auxiliary variables representing the digit carried over into the tens, hundreds, or thousands column

constraint hypergraph

The constraints can be represented in a **constraint hypergraph**

A hypergraph consists of ordinary nodes (the circles in the figure) and hypernodes (the squares), which represent n-ary constraints



Constraint satisfaction is a two step process.

1. First, constraints are discovered or propagated as far as possible throughout the system. Then if there is still not a solution search begins.
2. A guess about something is made and added as a new constraint. Propagation can then occur with this new constraint.

Constraint propagation also arise from the presence of inference rules that allow additional constraint to be inferred from the ones that are given.

Constraint propagation terminates for one of the two reasons:

- A contradiction may be detected. If the contradiction involves only those constraints that were given as part of problem specification then no solution exists.
- A propagation has run out of stream and there are no further changes that can be made on the basis of current knowledge.

At this point, the second step begins. Some hypothesis about a way to strengthen the constraints must be made.

constraint optimization problem

preference constraints: indicating which solutions are preferred

- Eg in university class-scheduling problem Prof. R might prefer teaching in the morning, whereas Prof. N prefers teaching in the afternoon.

Preference constraints can often be encoded as costs on individual variable assignments

- for example, assigning an afternoon slot for Prof. R costs 2 points against the overall objective function, whereas a morning slot costs 1.

CSPs with preferences can be solved with optimization search methods, either path-based or local is called a **constraint optimization problem**

CONSTRAINT PROPAGATION: INFERENCE IN CSPS

CSPs an algorithm can search or do a specific type of **inference** called **constraint propagation**

- using the constraints to reduce the number of legal values for a variable, which in turn can reduce the legal values for another variable, and so on
- Constraint propagation may be intertwined with search, or it may be done as a preprocessing step, before search starts.
- Sometimes this preprocessing can solve the whole problem, so no search is required at all

local consistency

- If we treat each variable as a node in a graph and each binary constraint as an arc, then
- the process of enforcing local consistency in each part of the graph causes inconsistent values to be eliminated throughout the graph

Node consistency

Node-consistent→ variable with the values in the variable's domain satisfy the variable's unary constraints.

Eg: variant of the Australia map-coloring problem with South Australians dislike green,

- the variable SA starts with domain {red, green, blue}, and
- we can make it node consistent by eliminating green, leaving SA with the reduced domain {red, blue}.

A network is node-consistent if every variable in the network is node-consistent

It is always possible to eliminate all the unary constraints in a CSP by running node consistency.

Arc consistency

A variable in a CSP is **arc-consistent** if every value in its domain satisfies the variable's binary constraints

Xi is arc-consistent with respect to another variable Xj

- if for every value in the current domain Di there is some value in the domain Dj that satisfies the binary constraint on the arc (Xi, Xj)

A network is arc-consistent if every variable is arc consistent with every other variable.

For example, consider the constraint $Y = X^2$ where the domain of both X and Y is the set of digits. The constraint can be written as:

(X, Y), {(0, 0),(1, 1),(2, 4),(3, 9))} .

To make X arc-consistent with respect to Y , we reduce X's domain to {0, 1, 2, 3}.

If we also make Y arc-consistent with respect to X, then Y 's domain becomes {0, 1, 4, 9} and the whole CSP is arc-consistent.

arc consistency can do nothing for the Australia map-coloring problem.

Consider the following inequality constraint on (SA,WA):

{(red, green),(red, blue),(green, red),(green, blue),(blue, red),(blue, green)}

No matter what value you choose for SA (or for WA), there is a valid value for the other variable.

So applying arc consistency has no effect on the domains of either variable.

AC-3 Algorithm for Arc Inconsistency

There is a queue of arcs to make every variable arc-consistent

1. Initially, the queue contains all the arcs in the CSP
2. AC-3 then pops off an arbitrary arc (Xi, Xj) from the queue and makes Xi arc-consistent with respect to Xj
3. If Di is unchanged, the algorithm just moves on to the next arc
4. B)Else if this revises Di (makes the domain smaller),
   a. then we add to the queue all arcs (Xk, Xi) where Xk is a neighbor of Xi
      - because the change in Di might enable further reductions in the domains of Dk
      - even if we have previously considered Xk
5. Else if Di is revised down to nothing,
   a. then we know the whole CSP has no consistent solution, and AC-3 can immediately return failure

6. Otherwise, we keep checking, trying to remove values from the domains of variables until no more arcs are in the queue
7. At that point, we are left with a CSP that is equivalent to the original CSP
   - Then they both have the same solutions but
   - the arc-consistent CSP will in most cases be faster to search because its variables have smaller domains.

```
function AC-3( csp) returns false if an inconsistency is found and true otherwise
  inputs: csp, a binary CSP with components (X, D, C)
  local variables: queue, a queue of arcs, initially all the arcs in csp

  while queue is not empty do
    (X_i, X_j) ← REMOVE-FIRST(queue)
    if REVISE(csp, X_i, X_j) then
      if size of D_i = 0 then return false
      for each X_k in X_i.NEIGHBORS - {X_j} do
        add (X_k, X_i) to queue
  return true
```

```
function REVISE( csp, X_i, X_j) returns true iff we revise the domain of X_i
  revised ← false
  for each x in D_i do
    if no value y in D_j allows (x,y) to satisfy the constraint between X_i and X_j then
      delete x from D_i
      revised ← true
  return revised
```

Figure 6.3 The arc-consistency algorithm AC-3. After applying AC-3, either every arc is arc-consistent, or some variable has an empty domain, indicating that the CSP cannot be solved. The name "AC-3" was used by the algorithm's inventor (Mackworth, 1977) because it's the third version developed in the paper.

Complexity of AC-3

Assume a CSP with n variables,

- each with domain size at most d, and
- with c binary constraints (arcs).
- Each arc (Xk, Xi) can be inserted in the queue only d times because Xi has at most d values to delete.

Checking consistency of an arc can be done in $O(d^2)$ time,

so we get $O(cd^3)$ total worst-case time.

Arc consistency can go a long way toward reducing the domains of variables, sometimes finding a solution (by reducing every domain to size 1) and sometimes finding that the CSP cannot be solved (by reducing some domain to size 0).

But for other networks, arc consistency fails to make enough inferences.

Consider the map-coloring problem on Australia, but with only two colors allowed, red and blue.

- Arc consistency can do nothing because every variable is already arc consistent:
  - each can be red with blue at the other end of the arc (or vice versa).
- But clearly there is no solution to the problem:
  - because Western Australia, Northern Territory and South Australia all touch each other,
  - we need at least three colors for them alone.

Arc consistency tightens down the domains using the arcs

Generalized Arc/Hyperarc Consistent

Arc consistency to handle n-ary rather than just binary constraints

A variable Xi is **generalized arc consistent** with respect to an n-ary constraint

- if for every value v in the domain of Xi there exists a tuple of values that is a member of the constraint, has all its values taken from the domains of the corresponding variables, and has its Xi component equal to v

Path consistency

Path consistency tightens the binary constraints by using implicit constraints that are inferred by looking at triples of variables.

A two-variable set {Xi, Xj} is path-consistent with respect to a third variable Xm if,

- for every assignment {Xi = a, Xj = b} consistent with the constraints on {Xi, Xj},
- there is an assignment to Xm that satisfies the constraints on {Xi, Xm} and {Xm, Xj}.

This is called path consistency because one can think of it as looking at a path from Xi to Xj with Xm in the middle.

Path consistency Fares in coloring the Australia map with two colors

We will make the set {WA, SA} path consistent with respect to NT.

We start by enumerating the consistent assignments to the set.

In this case, there are only two:

- {WA = red, SA = blue} and {WA = blue, SA = red}.

We can see that with both of these assignments NT can be neither red nor blue

- because it would conflict with either WA or SA.

Because there is no valid choice for NT, we eliminate both assignments, and we end up with no valid assignments for {WA, SA}.

Therefore, we know that there can be no solution to this problem

K-consistency

Stronger forms of propagation can be defined with the notion of k-**consistency**.

A CSP is k-consistent if, for any set of k − 1 variables and for any consistent assignment to those variables, a consistent value can always be assigned to any kth variable.

- 1-consistency says that, given the empty set, we can make any set of one variable consistent: this is what we called node consistency.
- 2-consistency is the same as arc consistency.
- For binary constraint networks, 3-consistency is the same as path consistency.

A CSP is strongly k-consistent if it is k-consistent and is also (k − 1)-consistent, (k − 2)-consistent, ... all the way down to 1-consistent.

suppose we have a CSP with n nodes and make it strongly n-consistent (i.e., strongly k-consistent for k = n).

We can then solve the problem as follows:

- First, we choose a consistent value for X1.
- We are then guaranteed to be able to choose a value for X2 because the graph is 2-consistent,
- for X3 because it is 3-consistent, and so on.
- For each variable Xi, we need only search through the d values in the domain to find a value consistent with X1,...,Xi−1.
- We are guaranteed to find a solution in time O(n2d).

Global constraints

global constraint is one involving an arbitrary number of variables but not necessarily all variables

Eg, in sudoku the Alldiffff constraint says that all the variables involved must have distinct values

One simple form of inconsistency detection for Alldiffff constraints works as follows:

- if m variables are involved in the constraint, and if they have n possible distinct values altogether, and m>n, then the constraint cannot be satisfied

Simple algorithm for global constraint

if m variables are involved in the constraint, and if they have n possible distinct values altogether, and m>n, then the constraint cannot be satisfied.

1. First, remove any variable in the constraint that has a singleton domain, and delete that variable's value from the domains of the remaining variables.
2. Repeat as long as there are singleton variables. If at any point an empty domain is produced or there are more variables than domain values left, then an inconsistency has been detected.

Resource constraint/ Atmost constraint

in a scheduling problem, let P1,...,P4 denote the numbers of personnel assigned to each of four tasks.

The constraint that no more than 10 personnel are assigned in total is written as Atmost(10, P1, P2, P3, P4).

We can detect an inconsistency simply by checking the sum of the minimum values of the current domains;

for example, if each variable has the domain {3, 4, 5, 6}, the Atmost constraint cannot be satisfied.

We can also enforce consistency by deleting the maximum value of any domain if it is not consistent with the minimum values of the other domains.

Thus, if each variable in our example has the domain {2, 3, 4, 5, 6}, the values 5 and 6 can be deleted from each domain

BOUNDS PROPAGATION

For large resource-limited problems it is usually not possible to represent the domain of each variable as a large set of integers and gradually reduce that set by consistency-checking methods

- E.g., logistical problems involving moving thousands of people in hundreds of vehicles

Instead, domains are represented by upper and lower bounds and are managed by **bounds propagation**

- Example
  - in an airline-scheduling problem, let's suppose there are two flights, F1 and F2, for which the planes have capacities 165 and 385, respectively.
  - The initial domains for the numbers of passengers on each flight are then
    - D1 = [0, 165] and D2 = [0, 385] .
  - Now suppose we have the additional constraint that the two flights together must carry 420 people: F1 + F2 = 420.
  - Propagating bounds constraints, we reduce the domains to
    - D1 = [35, 165] and D2 = [255, 385] .

420-385=35

420-165=255

We say that a CSP is bounds consistent

- if for every variable X, and for both the lower- bound and upper-bound values of X,
- there exists some value of Y that satisfies the constraint between X and Y for every variable Y .

This kind of bounds propagation is widely used in practical constraint problems.

Sudoku

A Sudoku board consists of 81 squares, some of which are initially filled with digits from 1 to 9.

The puzzle is to fill in all the remaining squares such that no digit appears twice in any row, column, or 3 × 3 box

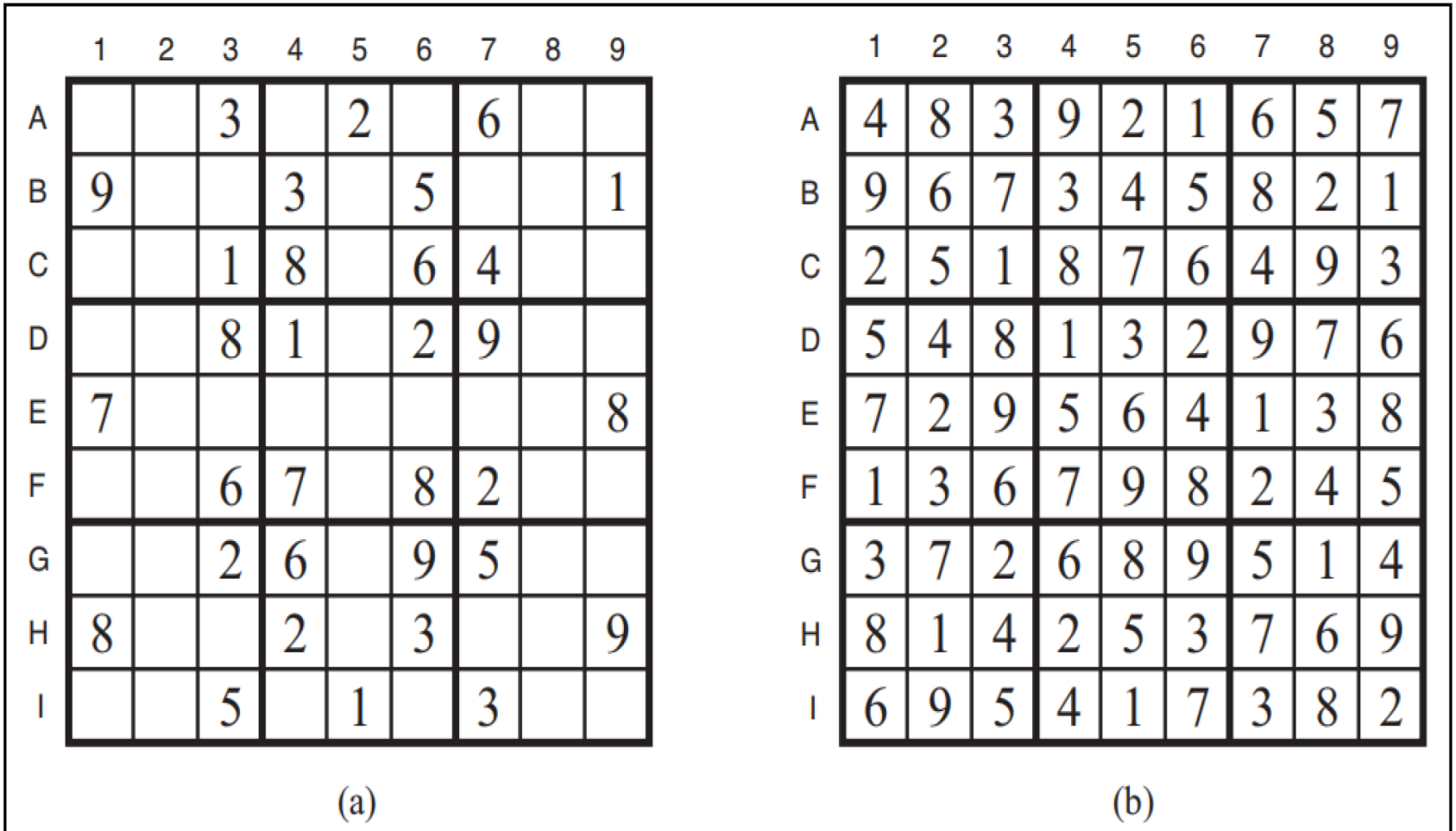
A row, column, or box is called a **unit**

even the hardest Sudoku problems yield to a CSP solver in less than 0.1 second

A Sudoku puzzle can be considered a CSP with 81 variables, one for each square.

We use the variable names A1 through A9 for the top row (left to right), down to I1 through I9 for the bottom row.

The empty squares have the domain {1, 2, 3, 4, 5, 6, 7, 8, 9} and the pre-filled squares have a domain consisting of a single value.



	1	2	3	4	5	6	7	8	9
A			3		2		6		
B	9			3		5			1
C			1	8		6	4		
D			8	1		2	9		
E	7								8
F			6	7		8	2		
G			2	6		9	5		
H	8			2		3			9
I			5		1		3		

(a)

	1	2	3	4	5	6	7	8	9
A	4	8	3	9	2	1	6	5	7
B	9	6	7	3	4	5	8	2	1
C	2	5	1	8	7	6	4	9	3
D	5	4	8	1	3	2	9	7	6
E	7	2	9	5	6	4	1	3	8
F	1	3	6	7	9	8	2	4	5
G	3	7	2	6	8	9	5	1	4
H	8	1	4	2	5	3	7	6	9
I	6	9	5	4	1	7	3	8	2

(b)

Figure 6.4 (a) A Sudoku puzzle and (b) its solution.

In addition, there are 27 different Alldiff constraints: one for each row, column, and box of 9 squares:

Alldiff(A1, A2, A3, A4, A5, A6, A7, A8, A9)

Alldiff(B1, B2, B3, B4, B5, B6, B7, B8, B9)

…

Alldiff(A1, B1, C1, D1, E1, F1, G1, H1, I1)

Alldiff(A2, B2, C2, D2, E2, F2, G2, H2, I2)

…

Alldiff(A1, A2, A3, B1, B2, B3, C1, C2, C3)

Alldiff(A4, A5, A6, B4, B5, B6, C4, C5, C6)

…

Assume that the Alldiffff constraints have been expanded into binary constraints (such as A1 = A2) so that we can apply the AC-3 algorithm

Consider variable E6 the empty square between the 2 and the 8 in the middle box.

- From the constraints in the box, we can remove not only 2 and 8 but also 1 and 7 from E6's domain.
- From the constraints in its column, we can eliminate 5, 6, 2, 8, 9, and 3.
- That leaves E6 with a domain of {4}; in other words, we know the answer for E6.

Now consider variable I6

- the square in the bottom middle box surrounded by 1, 3, and 3.
- Applying arc consistency in its column, we eliminate 5, 6, 2, 4 (since we now know E6 must be 4), 8, 9, and 3.
- We eliminate 1 by arc consistency with I5 , and we are left with only the value 7 in the domain of I6.
- Now there are 8 known values in column 6, so arc consistency can infer that A6 must be 1.

Inference continues along these lines, and eventually, AC-3 can solve the entire puzzle—all the variables have their domains reduced to a single value

Sudoku problems are designed to be solved by inference over constraints.

But many other CSPs cannot be solved by inference alone; there comes a time when we must search for a solution.

Backtracking Search for CSP

backtracking search algorithms that work on partial assignments

a standard depth-limited search can be applied

A state would be a partial assignment, and an action would be adding var = value to the assignment.

But for a CSP with n variables of domain size d,

the branching factor at the top level is nd because any of d values can be assigned to any of n variables.

At the next level, the branching factor is (n – 1)d, and so on for n levels.

We generate a tree with $n! \cdot d^n$ leaves, even though there are only d^n possible complete assignments!

Inference can be interwoven with search.

Commutativity- crucial property common to all CSPs

CSPs are all commutative. A problem is commutative if the order of application of any given set of actions has no effect on the outcome.

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A problem is commutative if the order of application of any given set of actions has no effect on the outcome.

CSPs are commutative because when assigning values to variables, we reach the same partial assignment regardless of order

we need only consider a single variable at each node in the search tree

Backtracking search

a depth-first search that chooses values for one variable at a time and backtracks when a variable has no legal values left to assign

It repeatedly chooses an unassigned variable, and then tries all values in the domain of that variable in turn, trying to find a solution.

If an inconsistency is detected, then BACKTRACK returns failure, causing the previous call to try another value.

Assignment

- Each state in a CSP is defined by an *assignment* of values to some or all of the variables, $\{X_i = v_i, X_j = v_j, \ldots\}$.
- An assignment that does not violate any constraints is called a *consistent* or *legal assignment*.
- A *complete assignment* is one in which every variable is assigned, and a *solution* to a CSP is a consistent, complete assignment.
- A *partial assignment* is one that assigns values to only some of the variables.

Backtracking Search for CSPs

- **Algorithm**

function **BACKTRACK**(*assignment*, *csp*) returns a *solution*, or *failure*

```
if assignment is complete, return assignment
else SELECT unassigned variable, var          //variable ordering
for each value in domain of a var             //value ordering
        if value is consistent with the assignment
                add {var = value} to assignment and
                        call BACKTRACK
                if BACKTRACK succeeds, return assignment
        else remove {var = value}
return failure
```

```
function BACKTRACKING-SEARCH(csp) returns a solution, or failure
  return BACKTRACK({ }, csp)

function BACKTRACK(assignment, csp) returns a solution, or failure
  if assignment is complete then return assignment
  var ← SELECT-UNASSIGNED-VARIABLE(csp)
  for each value in ORDER-DOMAIN-VALUES(var, assignment, csp) do
    if value is consistent with assignment then
      add {var = value} to assignment
      inferences ← INFERENCE(csp, var, value)
      if inferences ≠ failure then
        add inferences to assignment
        result ← BACKTRACK(assignment, csp)
        if result ≠ failure then
          return result
    remove {var = value} and inferences from assignment
  return failure
```

Figure 6.5 A simple backtracking algorithm for constraint satisfaction problems. The algorithm is modeled on the recursive depth-first search of Chapter 3. By varying the functions SELECT-UNASSIGNED-VARIABLE and ORDER-DOMAIN-VALUES, we can implement the general-purpose heuristics discussed in the text. The function INFERENCE can optionally be used to impose arc-, path-, or *k*-consistency, as desired. If a value choice leads to failure (noticed either by INFERENCE or by BACKTRACK), then value assignments (including those made by INFERENCE) are removed from the current assignment and a new value is tried.

Backtracking Search for CSPs- Example

```
function BACKTRACK(assignment, csp) returns a solution, or failure
    if assignment is complete, return assignment
    else SELECT unassigned variable, var          //variable ordering
    for each value in domain of a variable        //value ordering
        if value is consistent with the assignment
            add {var = value} to assignment and
                call BACKTRACK
            if BACKTRACK succeeds, return assignment
        else remove {var = value}
    return failure
```

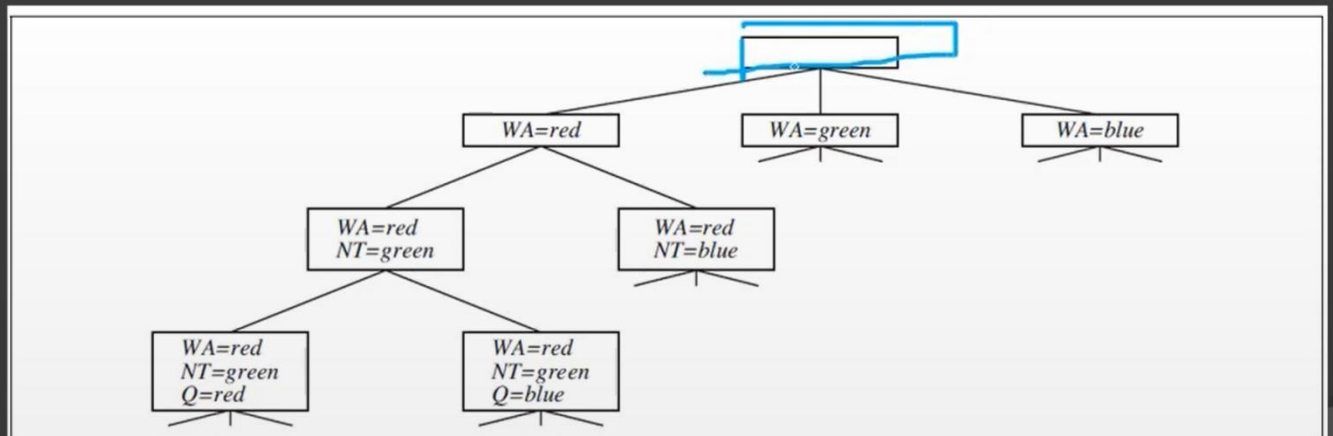


Figure 6.6 Part of the search tree for the map-coloring problem in Figure 6.1

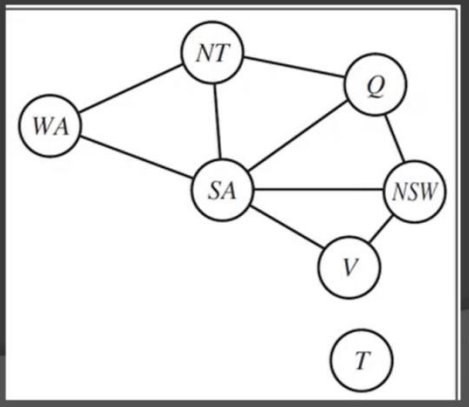
Unanswered questions

- Which variable should be assigned next (variable ordering)?
- In what order should its values be tried (value ordering)?
- What inferences should be performed at each step in the search (INFERENCE)?

Variable ordering

1. Minimum-Remaining-Values (MRV) heuristic

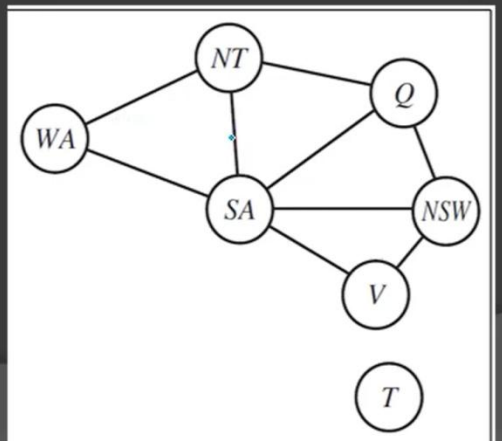
   - Chooses the variable with the fewest “legal” values
   - Also called the “most constrained variable” or “fail-first” heuristic
   - For example, after the assignments for WA=red and NT =green, there is only one possible value for SA, so it makes sense to assign SA=blue next rather than assigning Q. In fact, after SA is assigned, the choices for Q, NSW, and V are all forced.



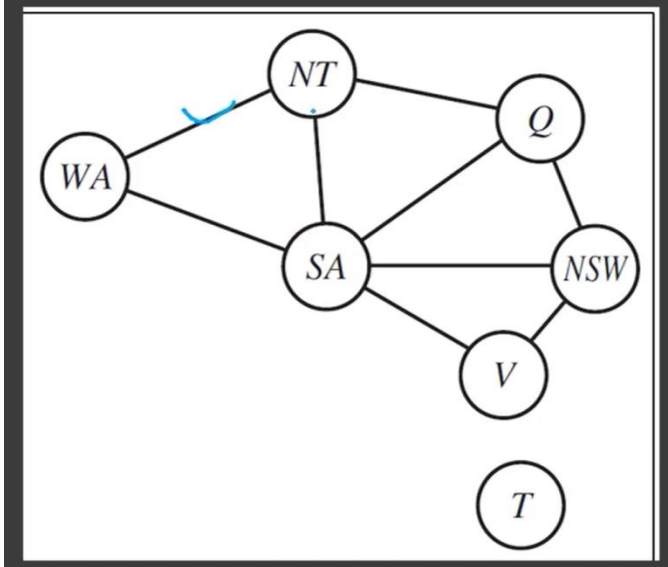
Variable ordering

2. Degree heuristic
   - selects the variable that is involved in the largest number of constraints on other unassigned variables
   - reduces the branching factor on future choices
   - E.g. SA is the variable with highest degree, 5. So, it will be chosen.

- The minimum-remaining-values heuristic is usually a more powerful guide, but the degree heuristic can be useful as a tie-breaker.



1. Defining Map coloring problem



Variables X = {WA,NT,Q,NSW, V,SA, T}

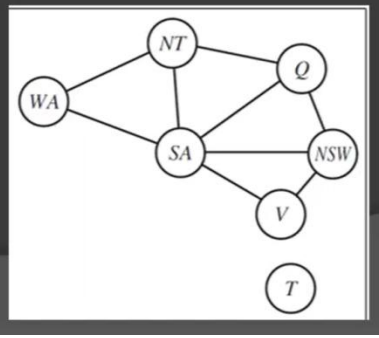
Domain of each variable is the set
D_i = {red, green, blue}.

Constraints:
C = {SA ≠ WA,SA ≠ NT,SA ≠ Q,SA ≠ NSW, SA ≠ V, WA ≠ NT,NT ≠ Q,Q ≠ NSW,NSW ≠ V } .

One possible solution is
{WA=red ,NT =green, Q=red ,NSW =green, V =red ,SA=blue, T =red }.

Value ordering

- Least-Constraining-Value heuristic
  - prefers the value that rules out the fewest choices for the neighboring variables in the constraint graph
  - For example, we have generated the partial assignment with WA=red and NT =green and that our next choice is for Q. Blue would be a bad choice because it eliminates the last legal value left for Q's neighbor, SA. The least-constraining-value heuristic therefore prefers red to blue.
  - In general, the heuristic is trying to leave the maximum flexibility for subsequent variable assignments.



Inference

- Forward Checking
  - Whenever a variable X is assigned, the forward-checking process establishes arc consistency for it: for each unassigned variable Y that is connected to X by a constraint, delete from Y 's domain any value that is inconsistent with the value chosen for X.

	WA	*NT*	*Q*	*NSW*	*V*	*SA*	*T*
Initial domains	R G B	R G B	R G B	R G B	R G B	R G B	R G B
After *WA*=*red*	(R)	G B	R G B	R G B	R G B	G B	R G B
After *Q*=*green*	(R)	B	(G)	R B	R G B	B	R G B
After *V*=*blue*	(R)	B	(G)	R	(B)		R G B

Figure 6.7 The progress of a map-coloring search with forward checking. $WA = red$ is assigned first; then forward checking deletes *red* from the domains of the neighboring variables NT and SA. After $Q = green$ is assigned, *green* is deleted from the domains of NT, SA, and NSW. After $V = blue$ is assigned, *blue* is deleted from the domains of NSW and SA, leaving SA with no legal values.

The Structure of Problems

- We examine ways in which the structure of the problem, as represented by the constraint graph, can be used to find solutions quickly

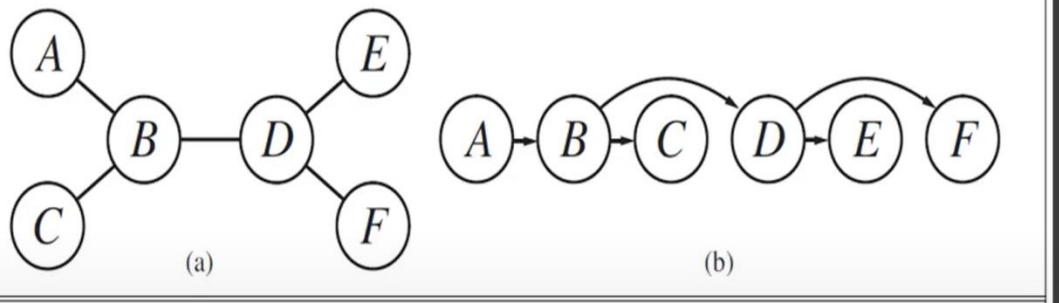


Figure 6.10 (a) The constraint graph of a tree-structured CSP. (b) A linear ordering of the variables consistent with the tree with A as the root. This is known as a **topological sort** of the variables.

DAC & Topological sort

- A constraint graph is a ***tree*** when any two variables are connected by only one path
- Any tree-structured CSP can be solved in linear time in the number of variables
- A CSP is defined to be *directed arc-consistent (DAC)* under an ordering of variables $X_1, X_2, \ldots, X_n$ if and only if every X_i is arc-consistent with each X_j for $j > i$.
- An ordering of the variables such that each variable appears after its parent in the tree. Such an ordering is called a *topological sort*.
- We have a directed arc-consistent (DAC) graph, we can just march down the list of variables and choose any remaining value. Since each link from a parent to its child is arc consistent, we know that for any value we choose for the parent, there will be a valid value left to choose for the child.

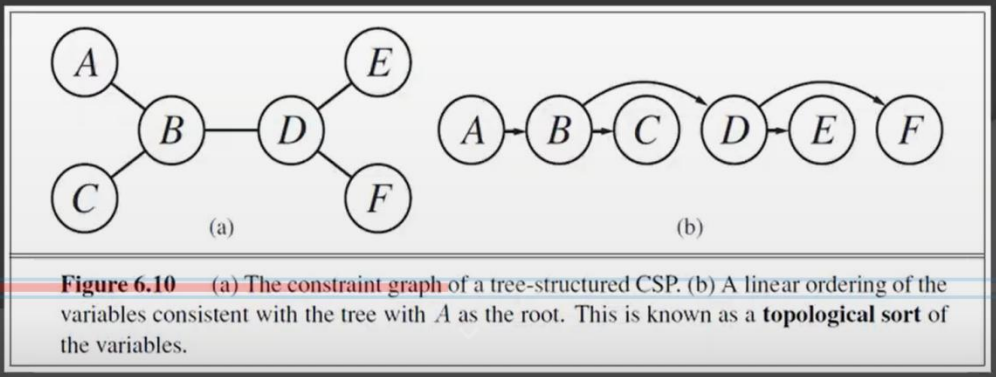


Figure 6.10 (a) The constraint graph of a tree-structured CSP. (b) A linear ordering of the variables consistent with the tree with A as the root. This is known as a **topological sort** of the variables.

TREE-CSP-SOLVER algorithm

function TREE-CSP-SOLVER(csp) **returns** a solution, or failure
  inputs: csp, a CSP with components X, D, C

  $n \leftarrow$ number of variables in X
  $assignment \leftarrow$ an empty assignment
  $root \leftarrow$ any variable in X
  $X \leftarrow$ TOPOLOGICALSORT(X, $root$)
  for j = n **down to** 2 **do**
    MAKE-ARC-CONSISTENT(PARENT(X_j), X_j)
    if it cannot be made consistent **then return** *failure*
  for i = 1 **to** n **do**
    $assignment[X_i] \leftarrow$ any consistent value from D_i
    if there is no consistent value **then return** *failure*
  return *assignment*

Figure 6.11 The TREE-CSP-SOLVER algorithm for solving tree-structured CSPs. If the CSP has a solution, we will find it in linear time; if not, we will detect a contradiction.

Two ways to reduce constraint graphs to trees

1. Cutset conditioning

The general algorithm is as follows:

1. Choose a subset S of the CSP's variables such that the constraint graph becomes a tree after removal of S. S is called a **cycle cutset**.
2. For each possible assignment to the variables in S that satisfies all constraints on S,

a) remove from the domains of the remaining variables any values that are inconsistent with the assignment for S, and

b) If the remaining CSP has a solution, return it together with the assignment for S.

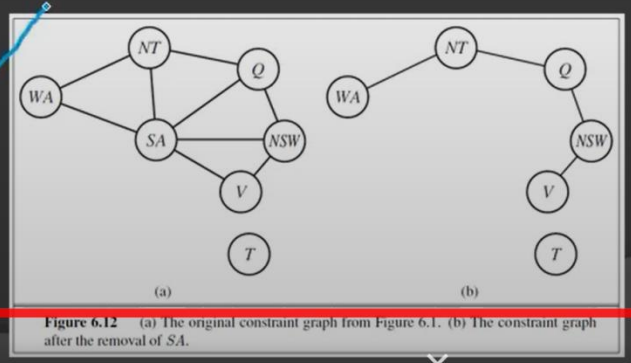


Figure 6.12 (a) The original constraint graph from Figure 6.1. (b) The constraint graph after the removal of *SA*.

Two ways to reduce constraint graphs to trees

2. Tree decomposition

A tree decomposition must satisfy the following three requirements:

- Every variable in the original problem appears in at least one of the subproblems.
- If two variables are connected by a constraint in the original problem, they must appear together (along with the constraint) in at least one of the subproblems.
- If a variable appears in two subproblems in the tree, it must appear in every subproblem along the path connecting those subproblems.

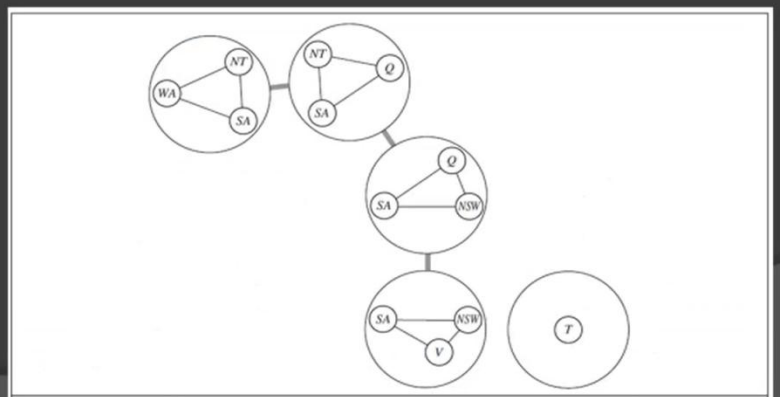


Figure 6.13 A tree decomposition of the constraint graph in Figure 6.12(a).

Tutorial 6

1. Give a precise formulation of the following constraint satisfaction problems:

   (a) Class scheduling: There is a fixed number of professors and classrooms, a list of classes to be offered, and a list of possible time slots for classes. Each professor has a set of classes that he or she can teach.

   Answer:

   The four variables in this problem are: Teachers, Subjects, Classrooms and Time slots.

   We can use two constraint matrices, T_{ij} and S_{ij}. T_{ij} represents a teacher in classroom i at time j. S_{ij} represents a subject being taught in classroom i at time j. The domain of each T_{ij} variable is the set of teachers. The domain of each S_{ij} variable is the set of subjects. Let's denote by $D(t)$ the set of subjects that teacher named t can teach.

   The constraints are:

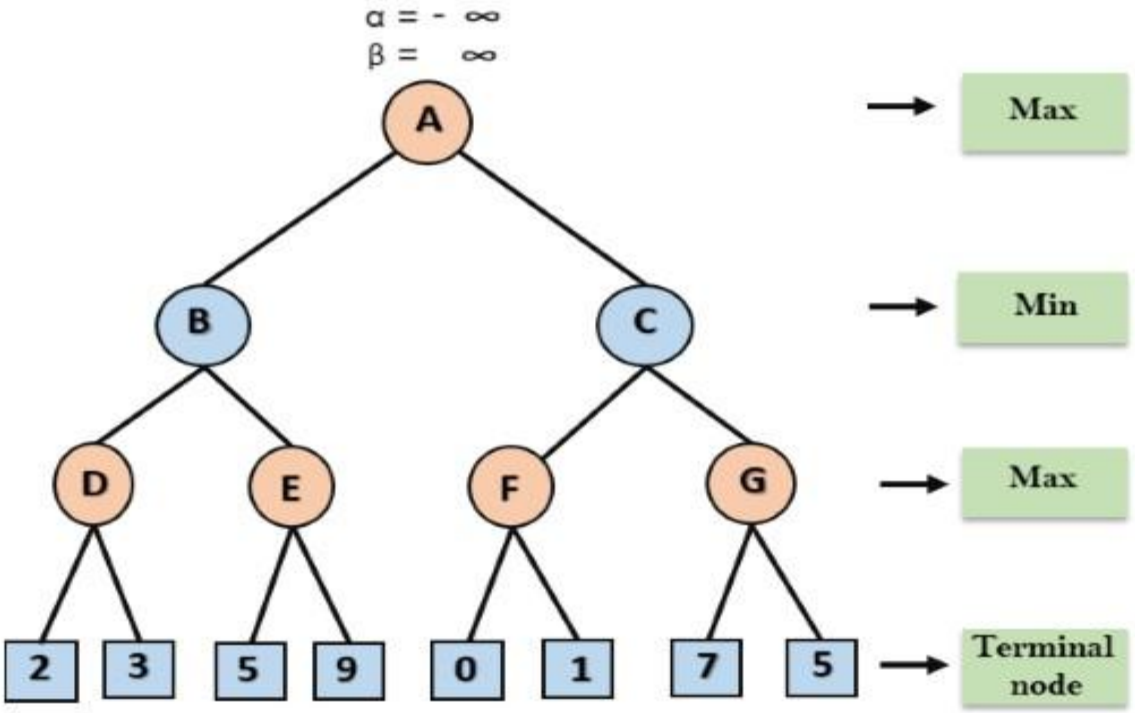
   $$T_{ij} \neq T_{kj} \quad k \neq i$$

   which enforces that no teacher is assigned to two classes which take place at the same time. There is a constraint between every S_{ij} and T_{ij}, denoted $C_{ij}(t, s)$ that ensured that if teacher t is assigned to T_{ij}, then S_{ij} is assigned a value from $D(t)$. An example for the constraint C is

   $$C(T_{ij}, S_{ij}) = \{(\text{Dechter}, 6a), (\text{Dechter}, 171), (\text{Dechter}, 175a), (\text{Smyth}, 171), (\text{Smyth}, 278), (\text{Irani}, 6a), \ldots\}$$

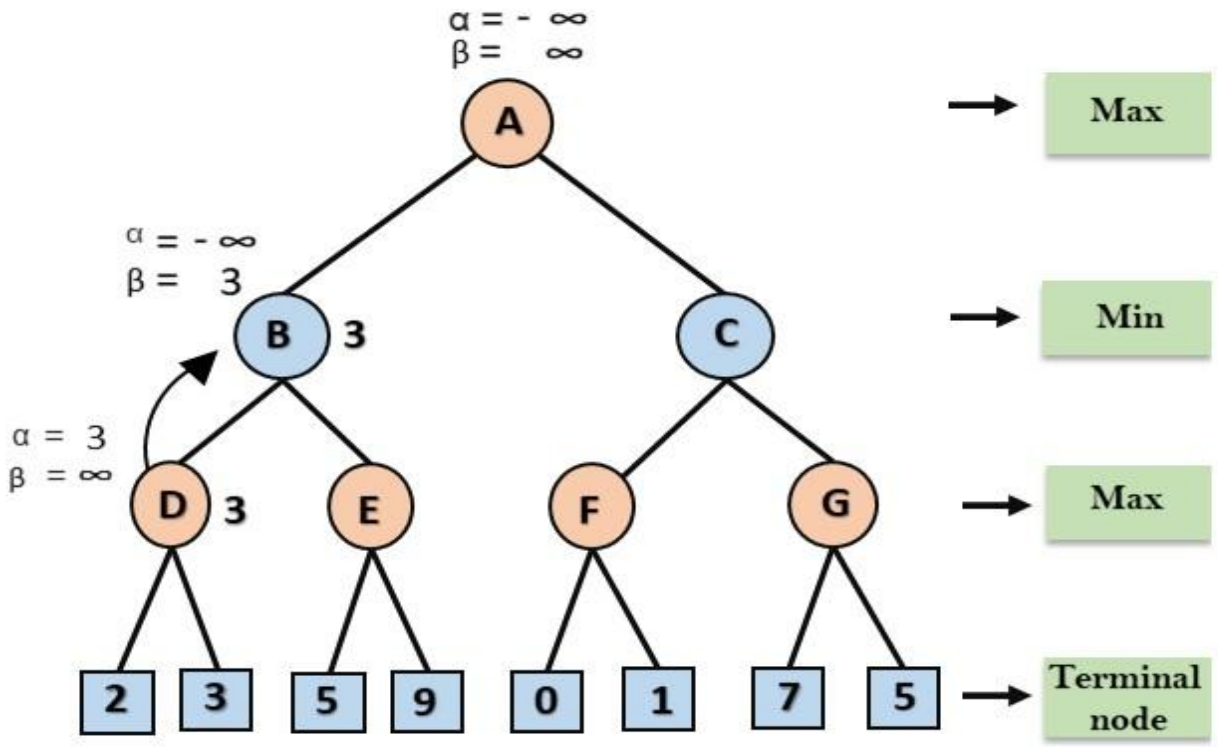
   In general $C(T_{ij}, S_{ij}) = \{(t, s) |\ \textit{teacher } t \textit{ can teach subject } s\}$

Step 1



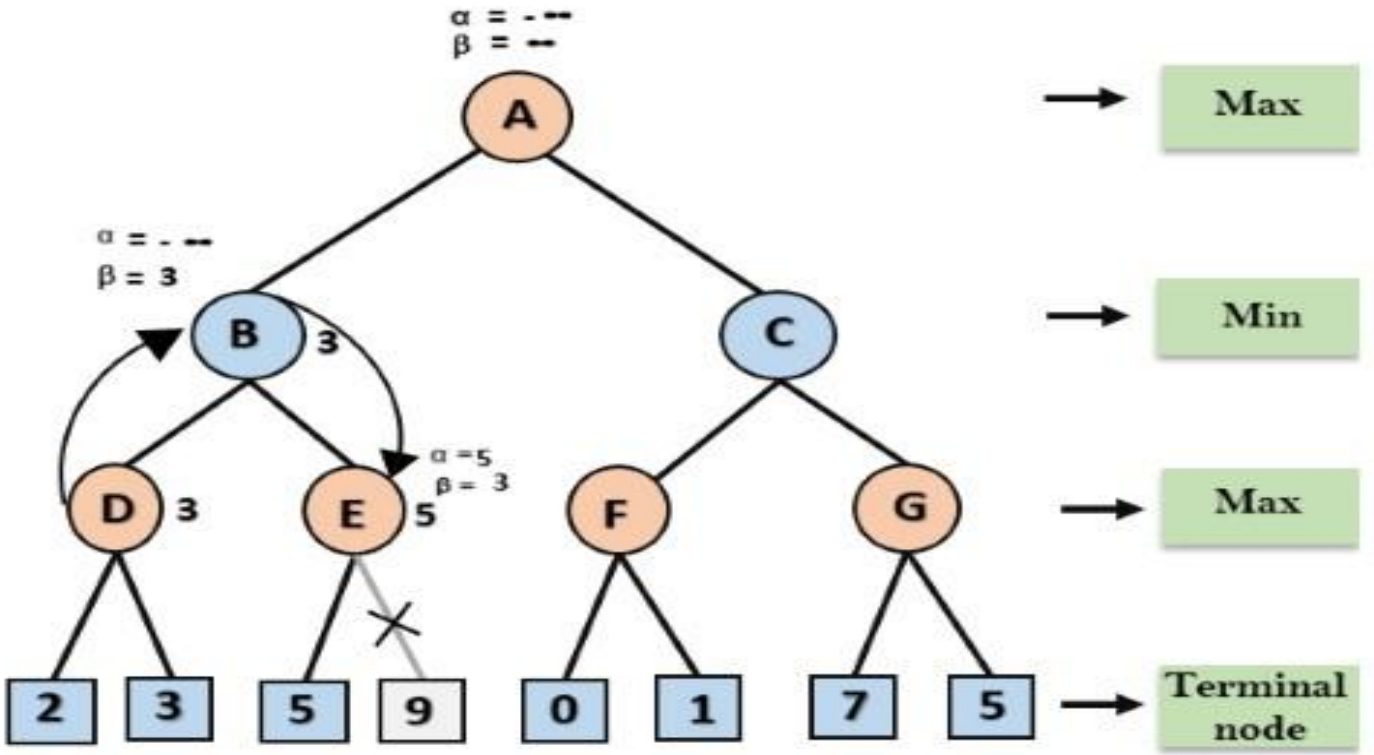
At the first step the, Max player will start first move from node A where α= -∞ and β= +∞, these value of alpha and beta passed down to node B where again α= -∞ and β= +∞, and Node B passes the same value to its child D.

Step2



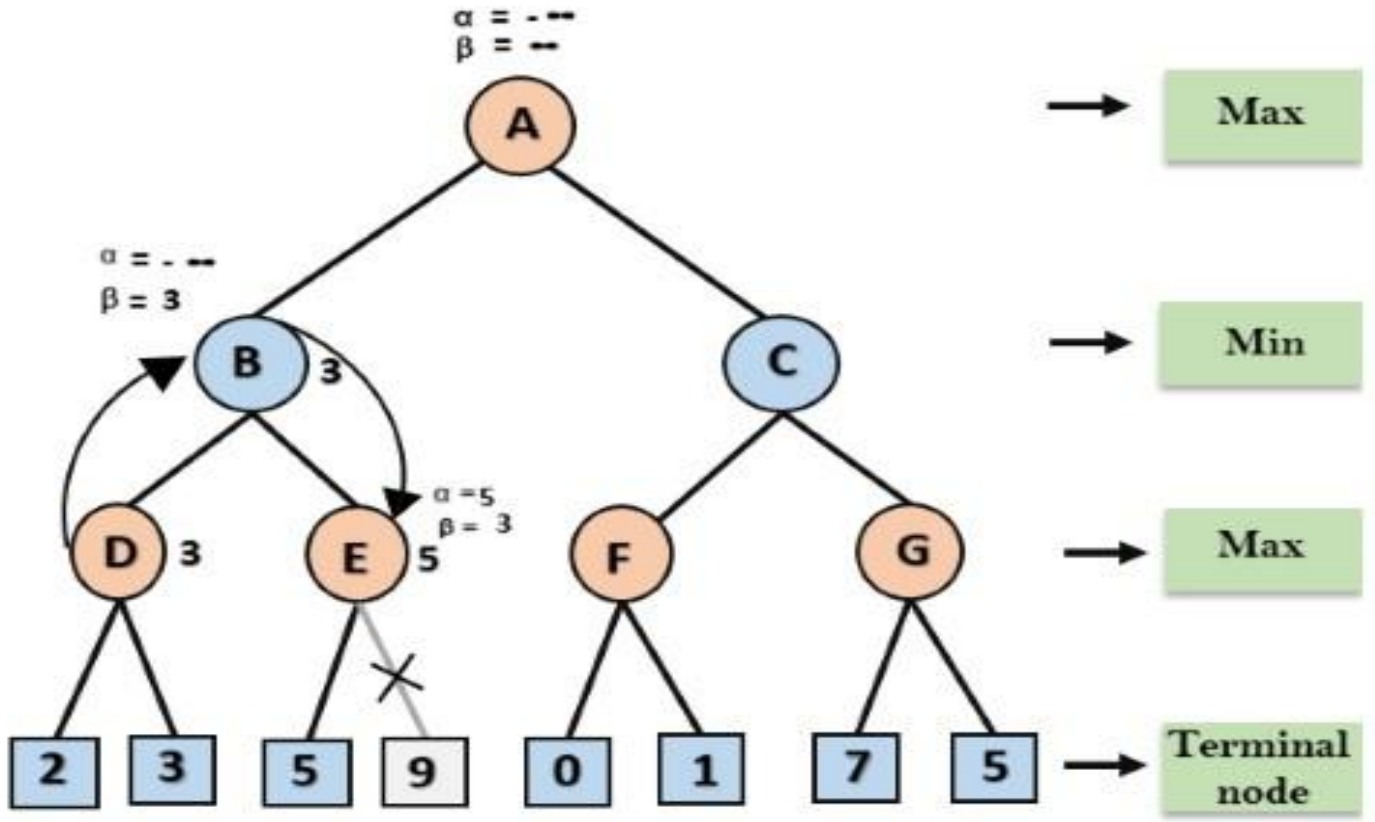
At Node D, the value of α will be calculated as its turn for Max. The value of α is compared with firstly 2 and then 3, and the max (2, 3) = 3 will be the value of α at node D and node value will also 3.

Step 3



Now algorithm backtrack to node B, where the value of β will change as this is a turn of Min, Now β= +∞, will compare with the available subsequent nodes value, i.e. min (∞, 3) = 3, hence at node B now α= -∞, and β= 3.

Step 4

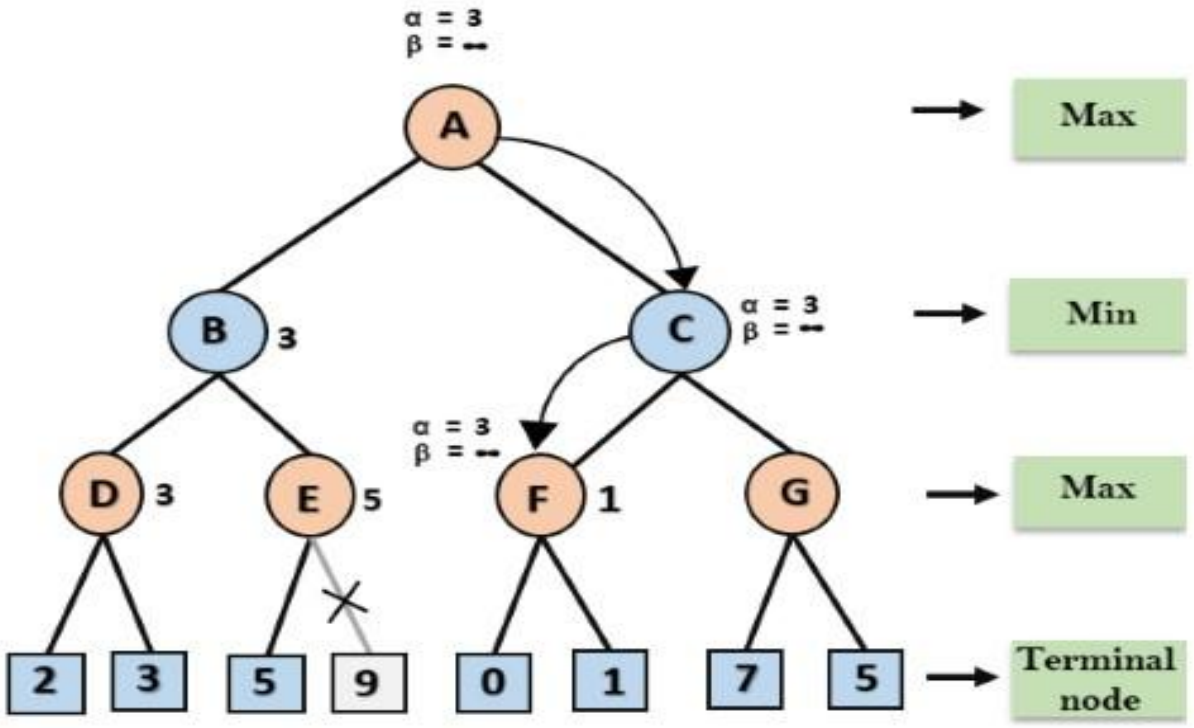


At node E, Max will take its turn, and the value of alpha will change. The current value of alpha will be compared with 5, so max (-∞, 5) = 5, hence at node E α= 5 and β= 3, where α>=β, so the right successor of E will be pruned, and algorithm will not traverse it, and the value at node E will be 5.

Step 5

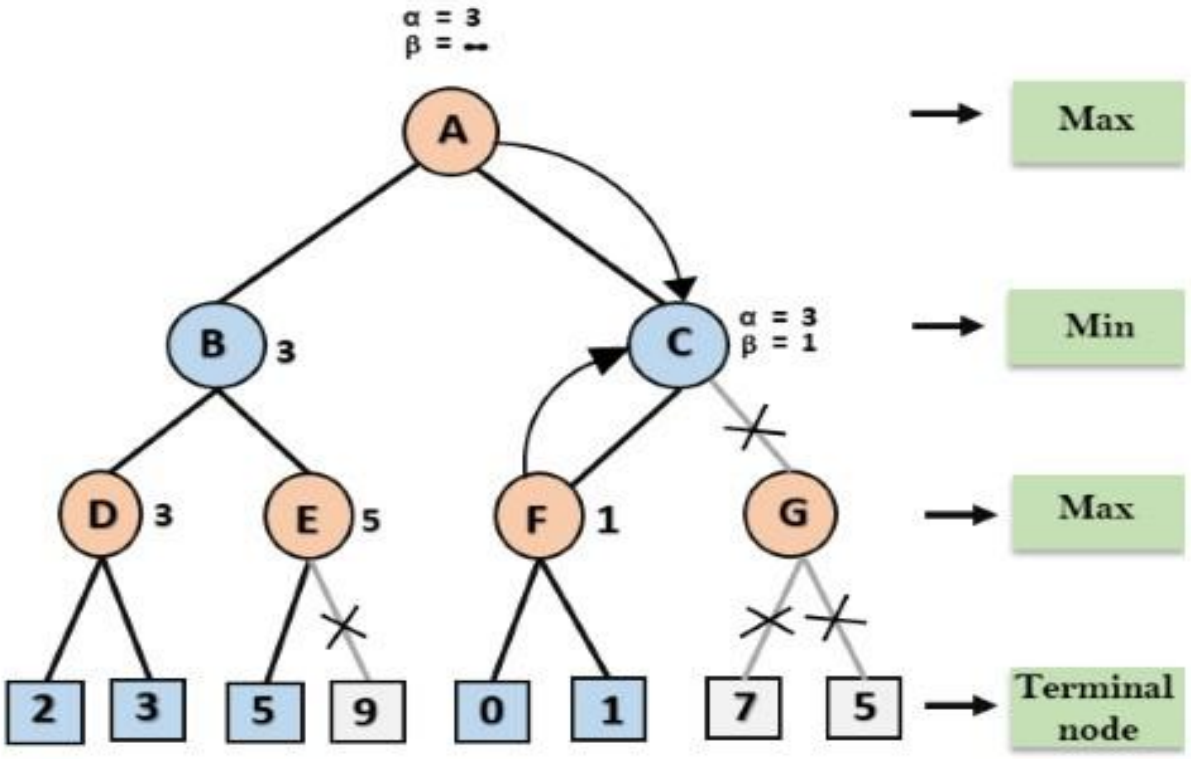
- At next step, algorithm again backtrack the tree, from node B to node A. At node A, the value of alpha will be changed the maximum available value is 3 as max (-∞, 3)= 3, and β= +∞, these two values now passes to right successor of A which is Node C.
- At node C, α=3 and β= +∞, and the same values will be passed on to node F.

Step 6



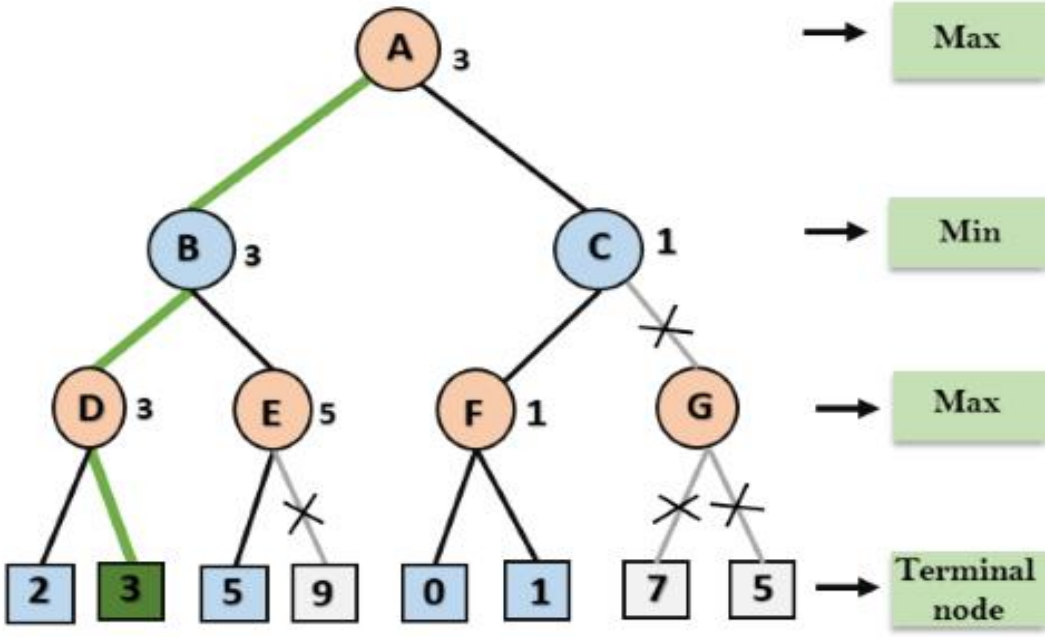
At node F, again the value of α will be compared with left child which is 0, and max(3,0)= 3, and then compared with right child which is 1, and max(3,1)= 3 still α remains 3, but the node value of F will become 1.

Step 7



Node F returns the node value 1 to node C, at C α= 3 and β= +∞, here the value of beta will be changed, it will compare with 1 so min (∞, 1) = 1. Now at C, α=3 and β= 1, and again it satisfies the condition α>=β, so the next child of C which is G will be pruned, and the algorithm will not compute the entire sub-tree G.

Step 8



C now returns the value of 1 to A here the best value for A is max (3, 1) = 3. Following is the final game tree which is the showing the nodes which are computed and nodes which has never computed. Hence the optimal value for the maximizer is 3 for this example.