

# Week 3 - Local Search, Planning Models & Languages

Due	No due date	Points	6	Questions	6	Time Limit	None
Allowed Attempts	Unlimited						

Take the Quiz Again

## Attempt History

	Attempt	Time	Score
LATEST	<a href="#">Attempt 1</a>	3 minutes	3 out of 6

Submitted Apr 20 at 10:29

Question 1

0 / 1 pts

WA\* uses  $f(n) = g(n) + w \cdot h(n)$ . Then, with  $w=0$  it becomes:

A\*

Uniform-cost search (Dijkstra)

Breadth-first search

Greedy Best First Search

Question 2

1 / 1 pts

WA\* with  $w = \text{infinity}$  becomes

☐ A\*

☐ Uniform-cost search (Dijkstra)

☐ Breadth-first search

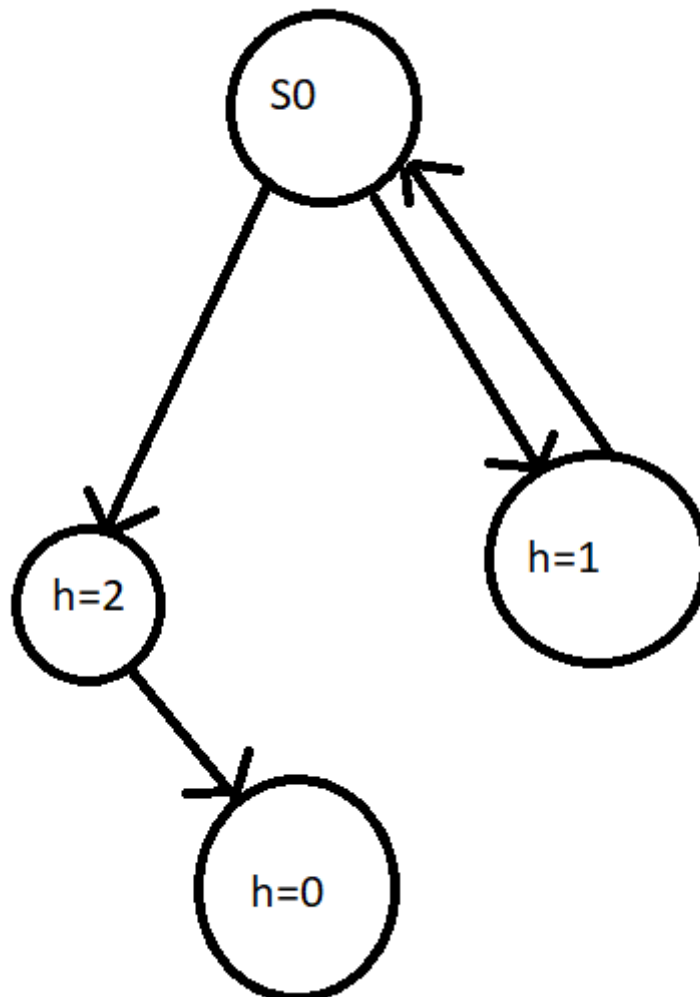
☒ Greedy Best First Search

Correct!

### Question 3

1 / 1 pts

For the following graph, assuming the  $h=0$  node is the goal, Enforced Hill Climbing is guaranteed to find a solution



Correct!

☒ Yes

☐ No

We can guarantee the search will never get stuck in a state that doesn't lead to the goal, as a path can be found from every state to the goal.

#### Question 4

0 / 1 pts

Conformant Planning has:

☐ A set of possible initial states and a probabilistic transition function

☐

A set of possible initial states and a non-deterministic transition function

☒

A probability distribution over the initial states and a probabilistic transition function

☐

A probability distribution over the initial states and a non-deterministic transition function

Correct Answer

You Answered

#### Question 5

1 / 1 pts

POMDPs have:

Correct!



A sensor model given by probabilities drawn from observations about the environment



A set of possible initial states



A deterministic transition function

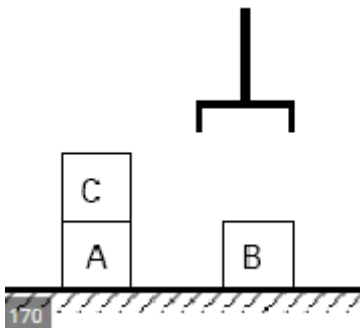


A complexity that is identical to classical planning

### Question 6

0 / 1 pts

Given the following initial state in a Blocks World problem, how many propositions are required to specify the initial state



you Answered

4

Correct Answers

6 (with margin: 0)

The following are required: onTable(A), on(C, A), onTable(B), clear(C), clear(B), armEmpty