

Uninformed Search

CS5491: Artificial Intelligence
ZHICHAO LU

Content Credits: Prof. Wei's CS4486 Course
and Prof. Boddeti's AI Course

TODAY (PART 1)

Uninformed Search

- › Search Trees
- › Search Algorithm Properties
- › Depth First Search
- › Breadth First Search
- › Uniform Cost Search



XKCD

Reading

- › Today's Lecture: RN Chapter 3.3-3.4

STATE SPACE GRAPHS AND SEARCH TREES

STATE SPACE GRAPHS

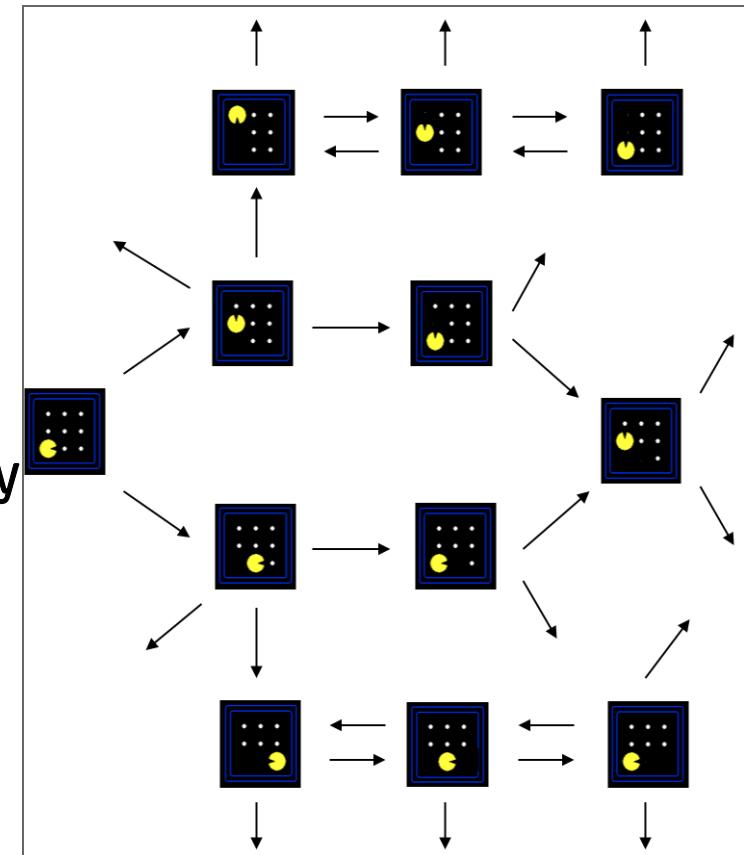
State Space Graph: A mathematical representation of a search problem

- Nodes are (abstracted) world configurations
 - Arcs represent successors (action results)
 - The goal test is a set of goal nodes (maybe only one)

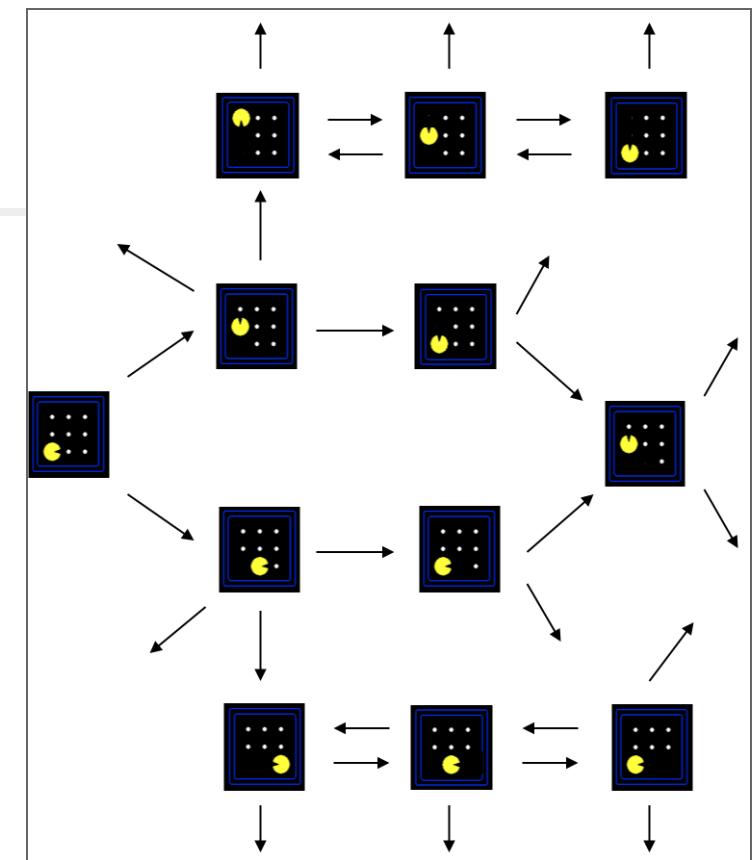
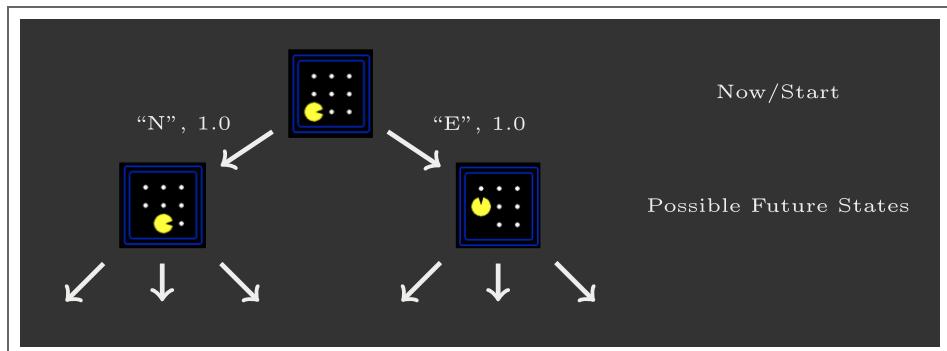
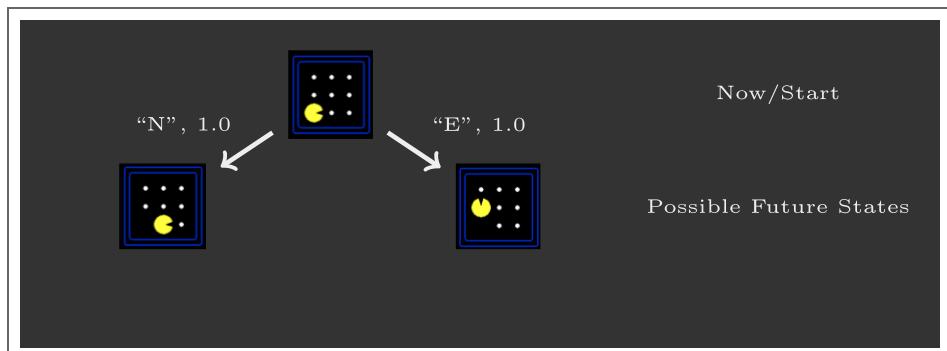
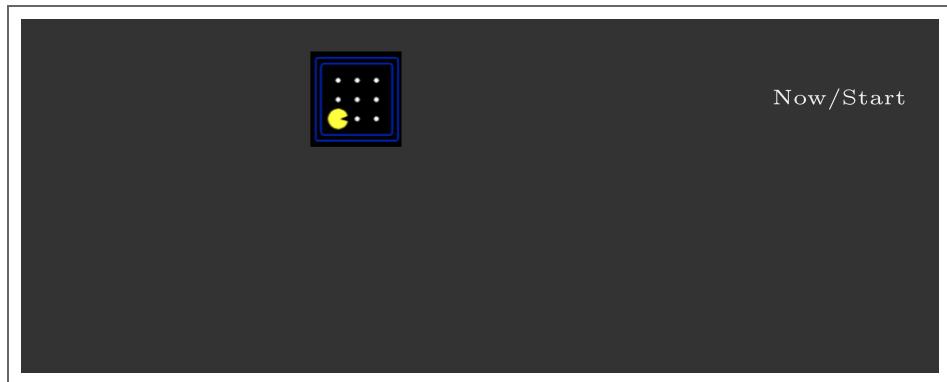
In a state space graph, each state occurs only once

We can rarely build this full graph in memory
(too big), but it is a useful idea

Tiny state space graph for a tiny search problem

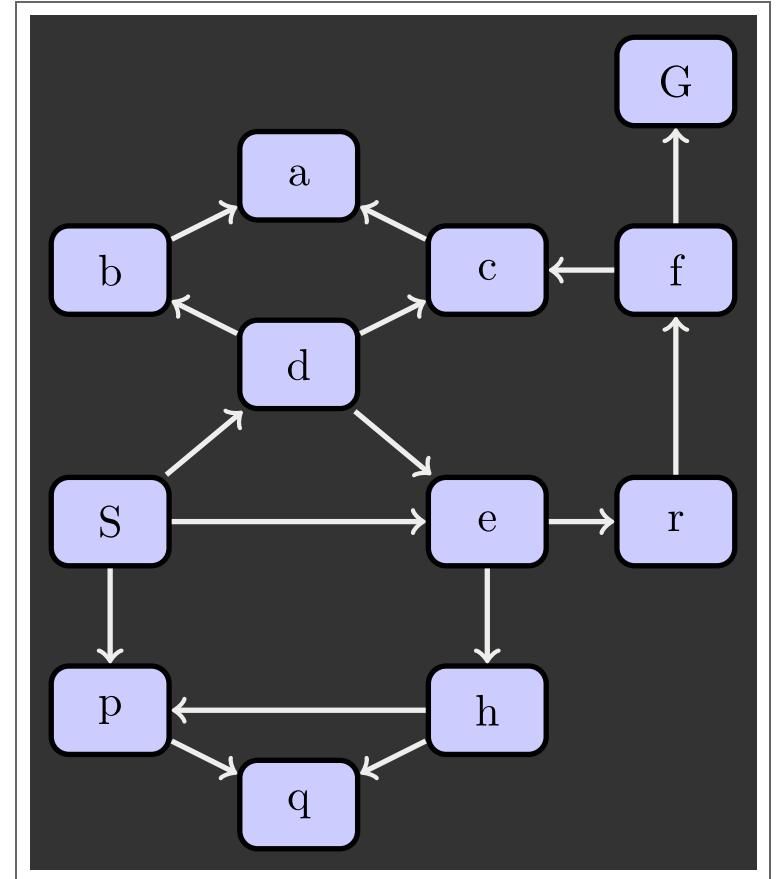


SEARCH TREES



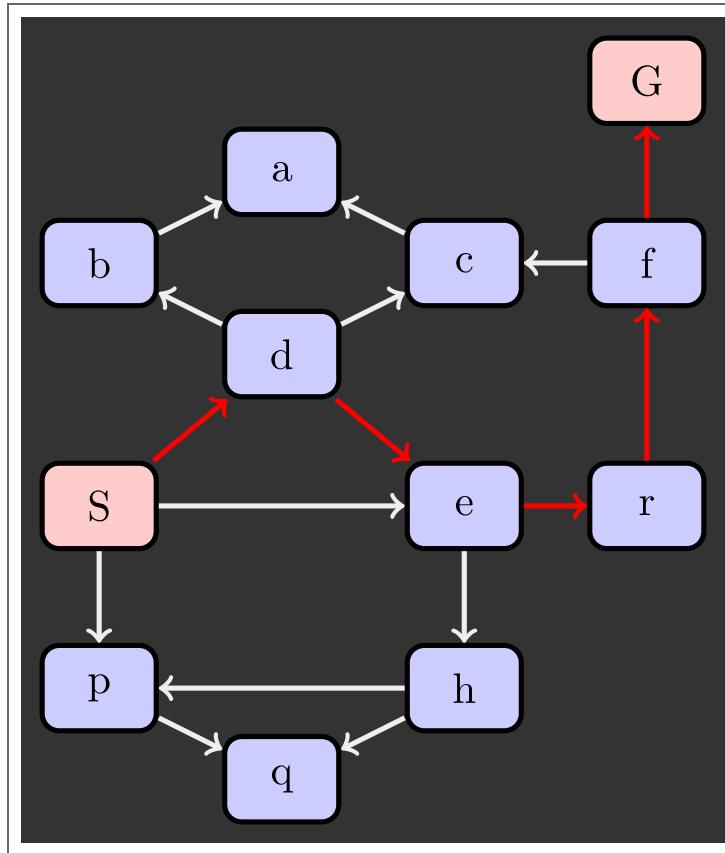
A search tree :

- › A “what if” tree of plans and their outcomes
- › The start state is the root node
- › Child nodes correspond to successors
- › Nodes show states, but correspond to **plans/actions** that achieve those states
- › Building the **whole tree is impossible for most problems**

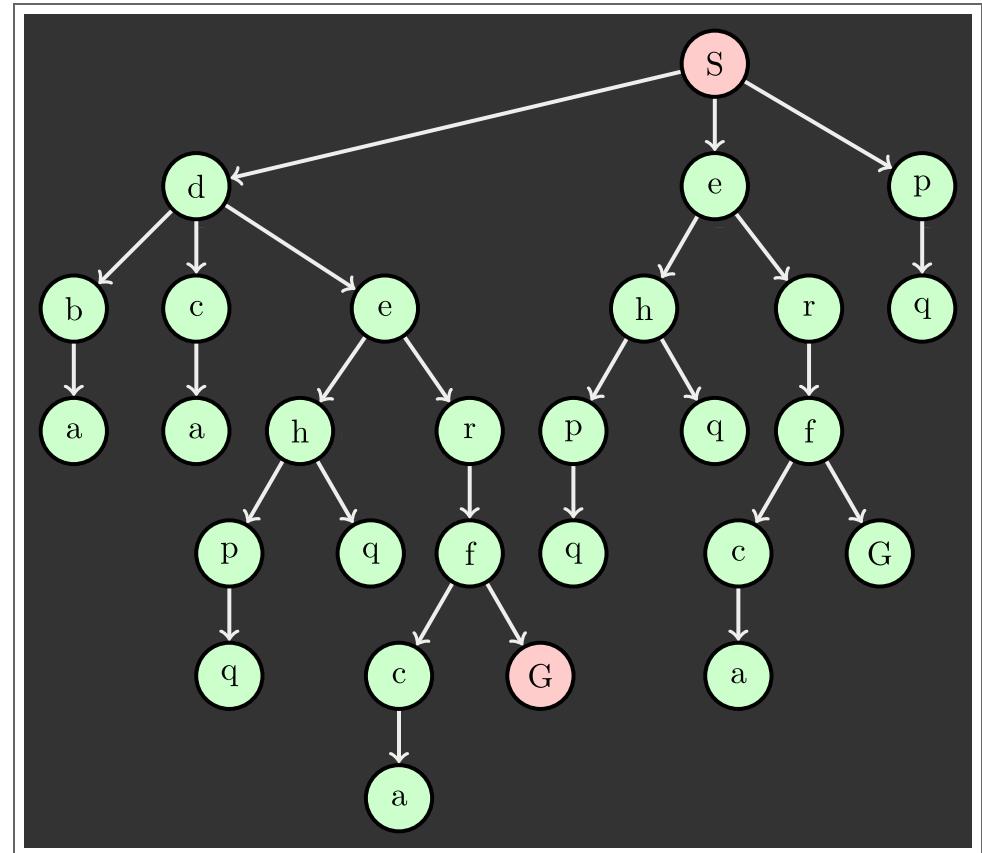


STATE SPACE VS SEARCH TREES

State Space Graph



Search Tree

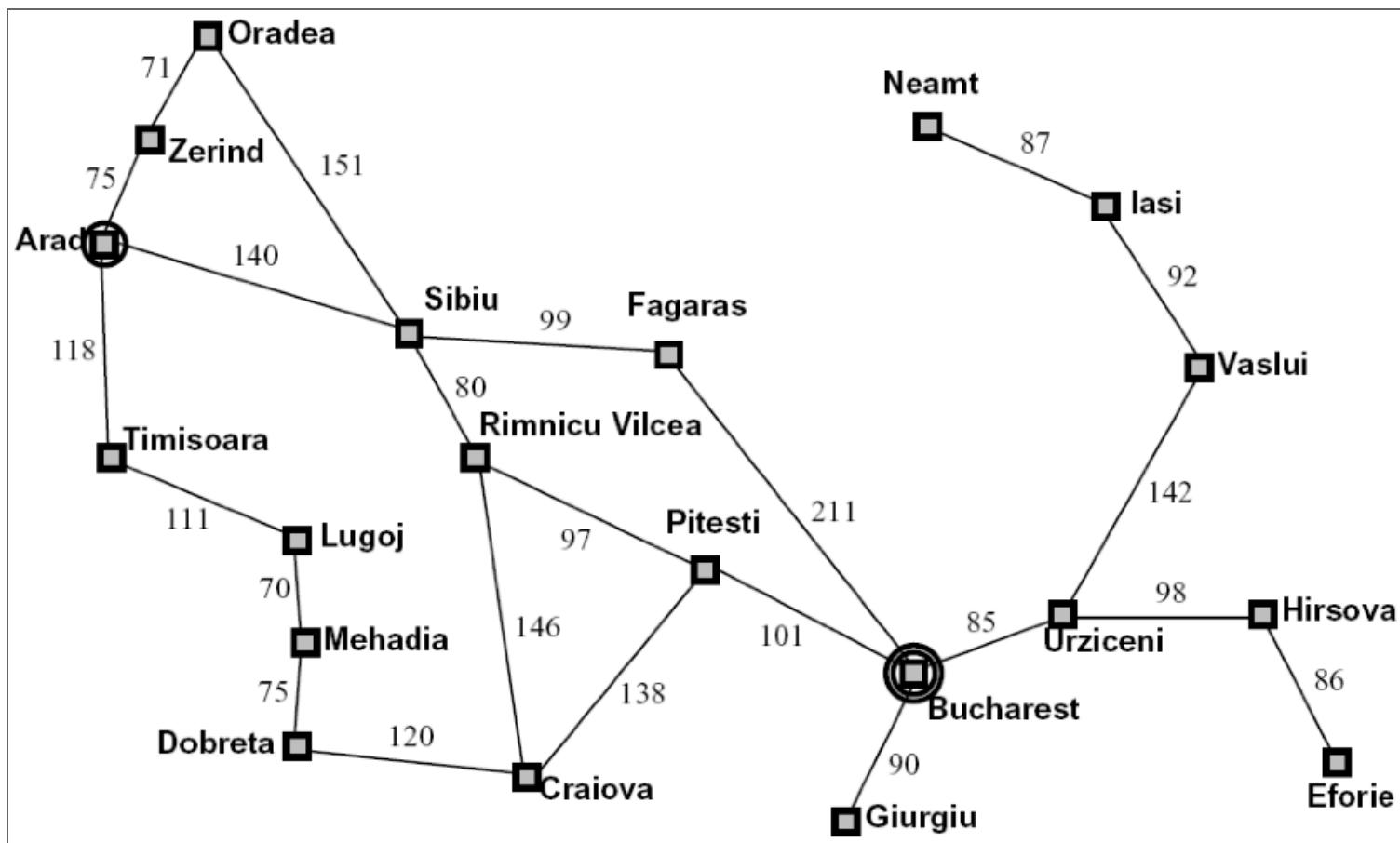


Each NODE in search tree is an entire PATH in state space graph.

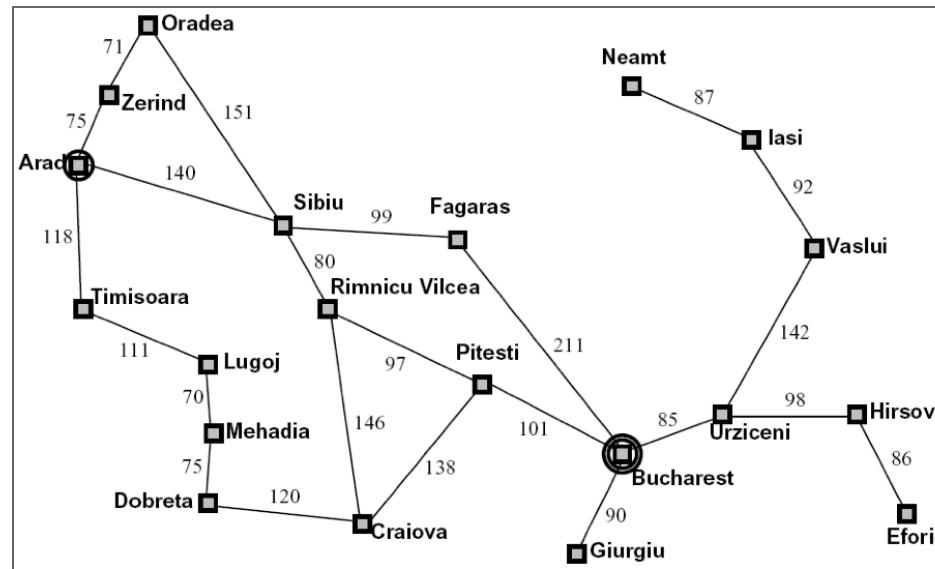
Construct both on demand – and construct as little as possible.

TREE SEARCH

SEARCH EXAMPLE: TRAVELING IN ROMANIA



SEARCH TREE: TRAVELING IN ROMANIA



Search:

- Expand out potential plans (tree nodes)
- Maintain a **fringe** of partial plans under consideration
- Try to expand as few tree nodes as possible

TREE SEARCH ALGORITHM

Tree Search

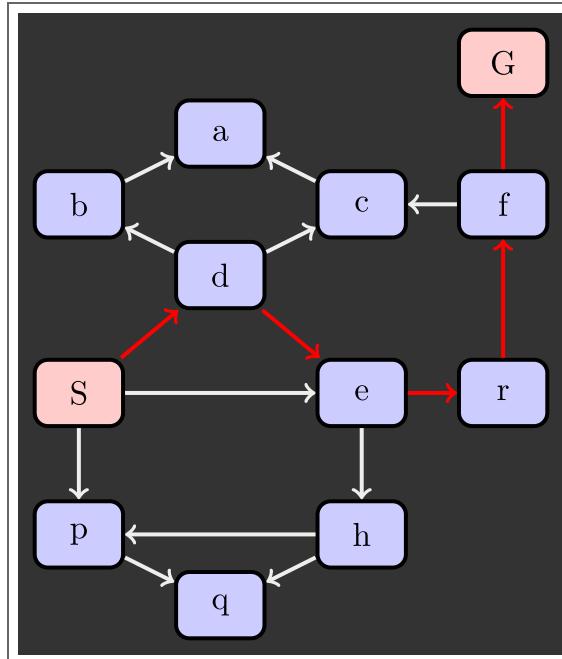
```
input : problem, strategy
output: solution or failure
initialize the search tree using initial state of problem;
while forever do
    if there are no candidates for expansion then return failure;
    choose a leaf node for expansion according to strategy;
    if node contains a goal state then
        | return the corresponding solution;
    else
        | expand the node and add the resulting nodes to the
          | search tree;
    end
end
```

Important Ideas:

- Fringe
- Expansion
- Exploration Strategy

Main question: which fringe nodes to explore?

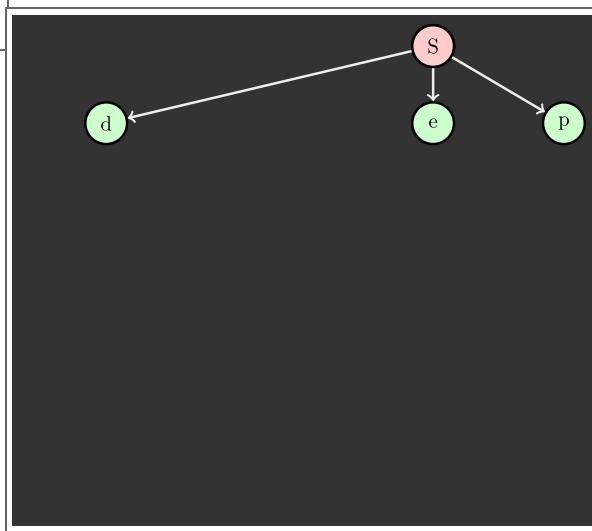
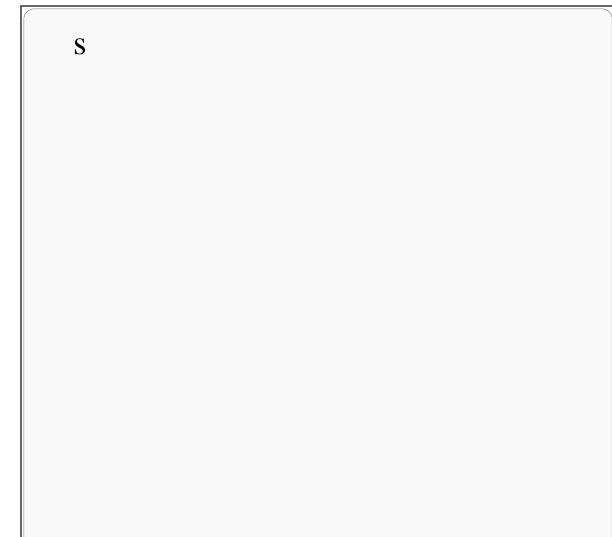
TREE SEARCH EXAMPLE



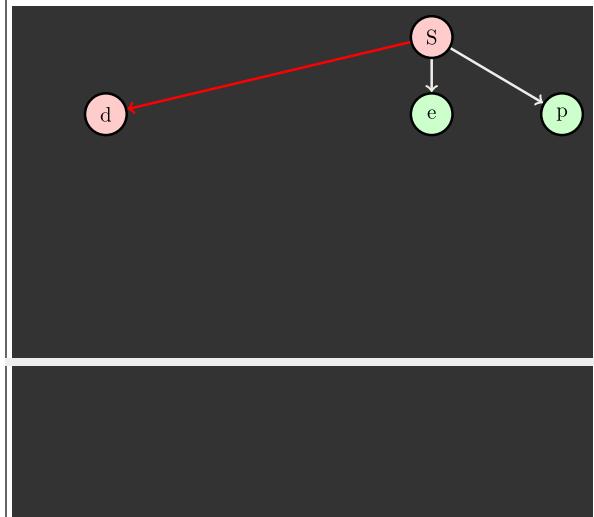
Search Tree



Search Tree Build

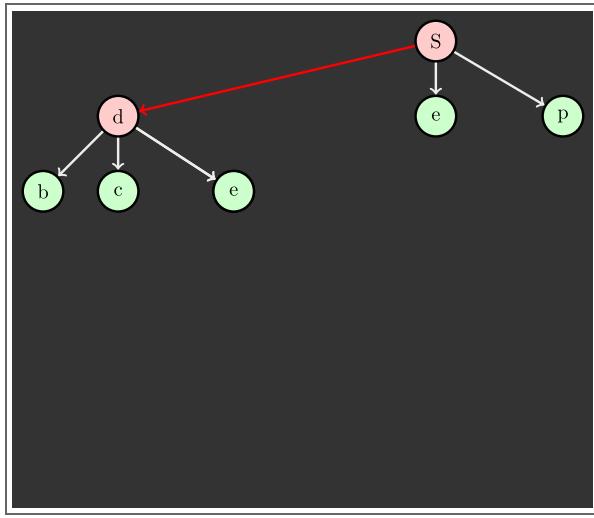


s
s → d
s → e
s → p

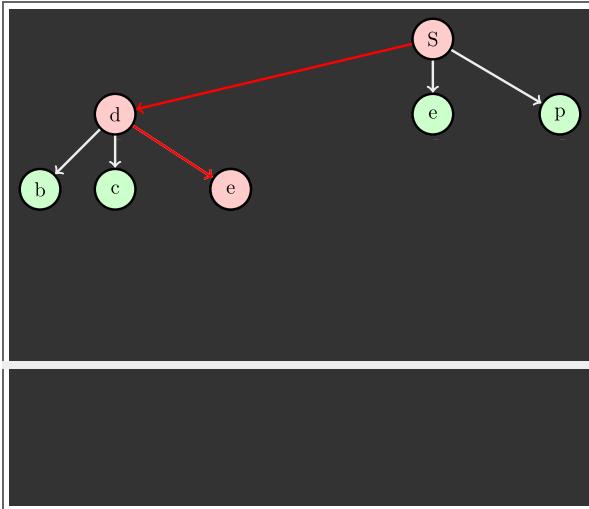


SEARCH ALGORITHM PROPERTIES

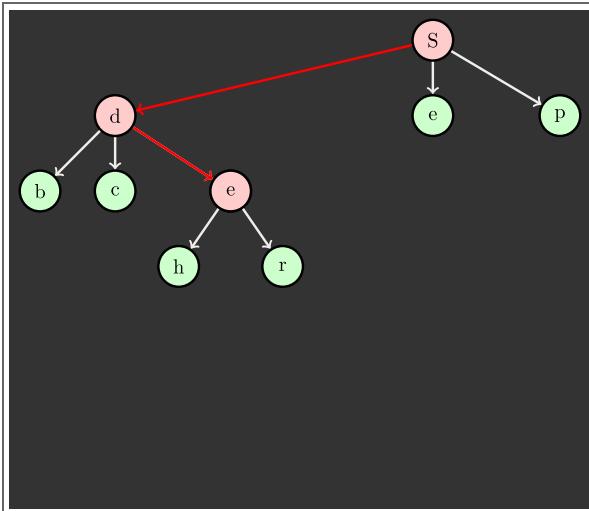
s (insert)
s → d
s → e
s → p



s (insert)
s → d
s → e
s → p
s → d → b
s → d → c
s → d → e



SEARCH ALGORITHM PROPERTIES



Complete: Guaranteed to find a solution if one exists?

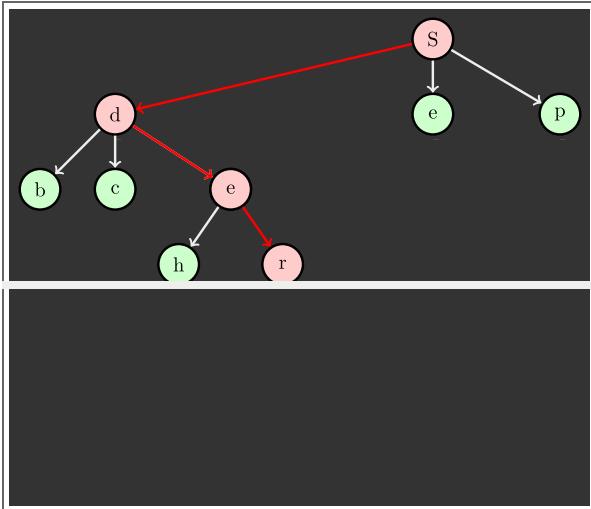
Optimal: Guaranteed to find the least cost path?

Time Complexity?

Space Complexity?

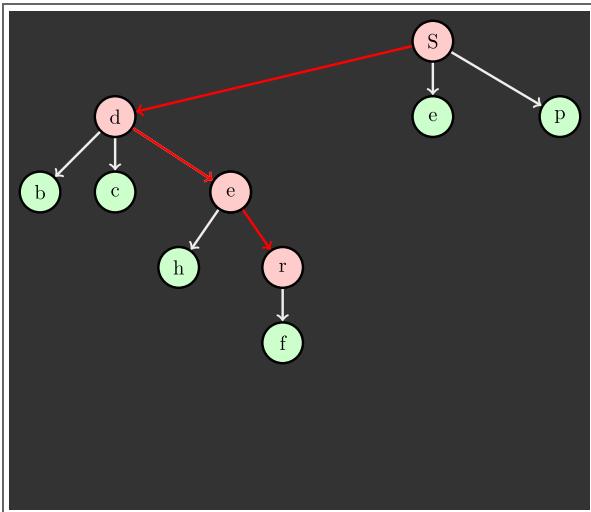
s (insert)
s → d (insert)
s → e
s → p
s → d → b
s → d → c
s → d → e

s (insert)
s → d (insert)
s → e
s → p
s → d → b
s → d → c
s → d → e
s → d → e → h
s → d → e → r

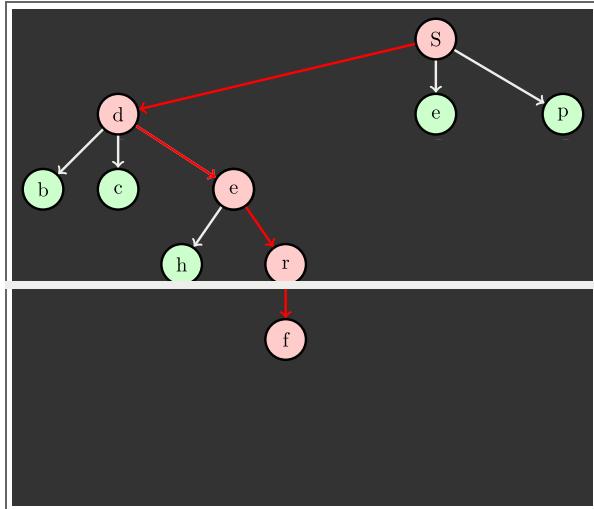


DEPTH-FIRST SEARCH

s (insert)
s → d (insert)
s → e
s → p
s → d → b
s → d → c
s → d → e (insert)
s → d → e → h
s → d → e → r



s (insert)
s → d (insert)
s → e
s → p
s → d → b
s → d → c
s → d → e (insert)
s → d → e → h
s → d → e → r
s → d → e → r → f



DEPTH FIRST SEARCH

s (insert)

s → d (insert)

s → e

s → p

s → d → b

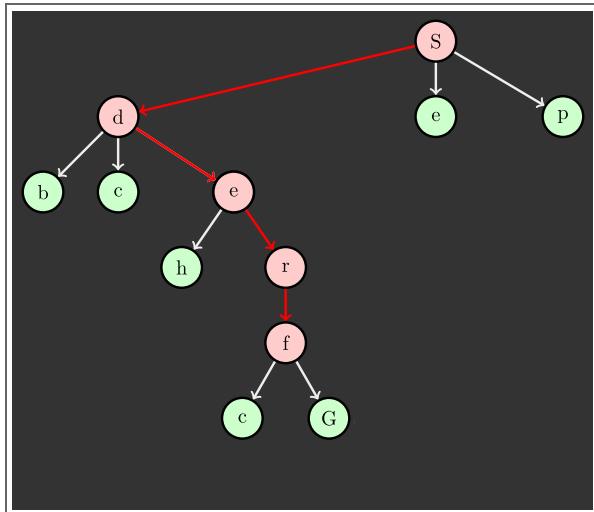
s → d → c

s → d → e (insert)

s → d → e → h

s → d → e → r (insert)

s → d → e → r → f



s (insert)

s → d (insert)

s → e

s → p

s → d → b

s → d → c

s → d → e (insert)

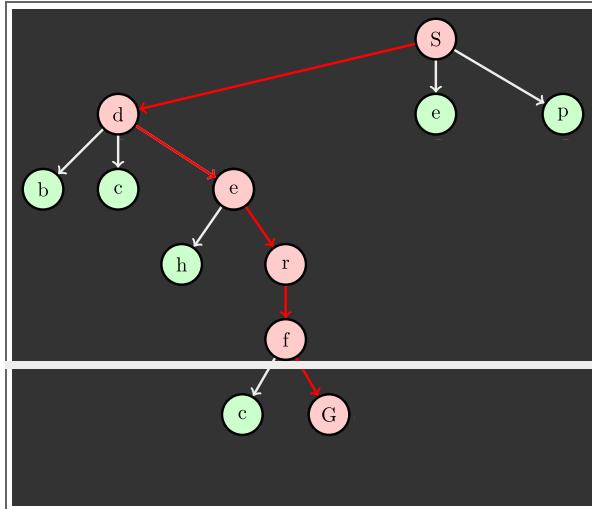
s → d → e → h

s → d → e → r (insert)

s → d → e → r → f

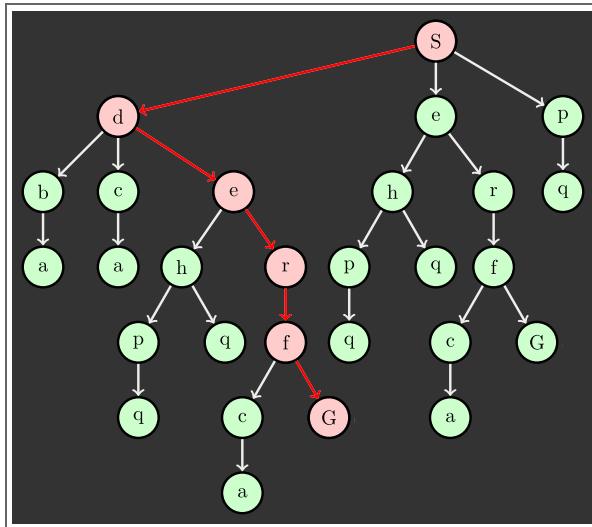
s → d → e → r → f → c

s → d → e → r → f → G



DEPTH-FIRST SEARCH (DFS) PROPERTIES

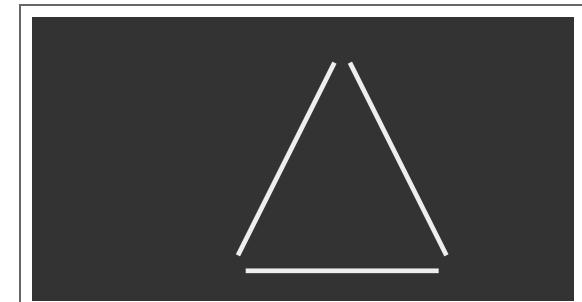
s (insert)
 s → d (insert)
 s → e
 s → p
 s → d → b
 s → d → c
 s → d → e (insert)
 s → d → e → h
 s → d → e → r (insert)
 s → d → e → r → f (insert)
 s → d → e → r → f → c
 s → d → e → r → f → G



s (insert)
 s → d (insert)
 s → e
 s → p
 s → d → b
 s → d → c
 s → d → e (insert)
 s → d → e → h
 s → d → e → r (insert)
 s → d → e → r → f (insert)
 s → d → e → r → f → c
 s → d → e → r → f → G (insert)

Cartoon of search tree:

- b is the branching factor
- m is the maximum depth

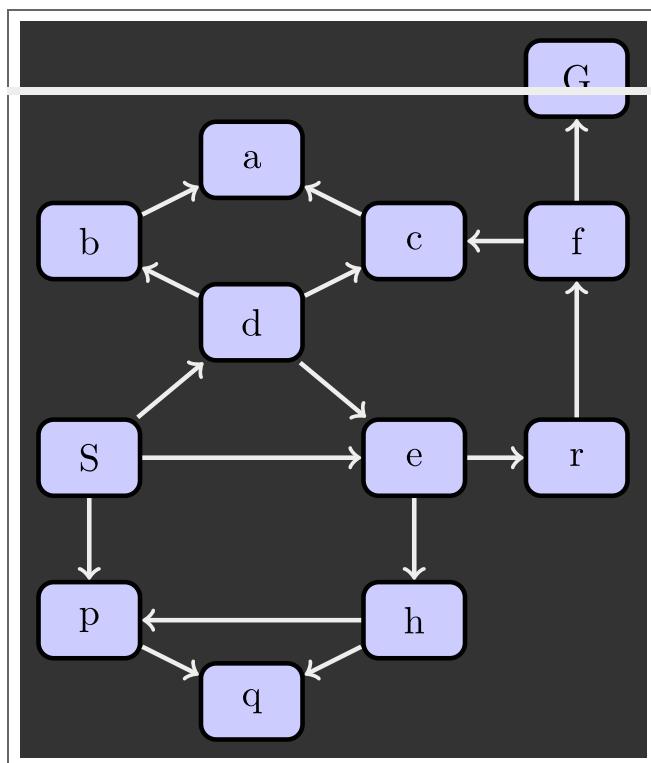


- solutions at various depths

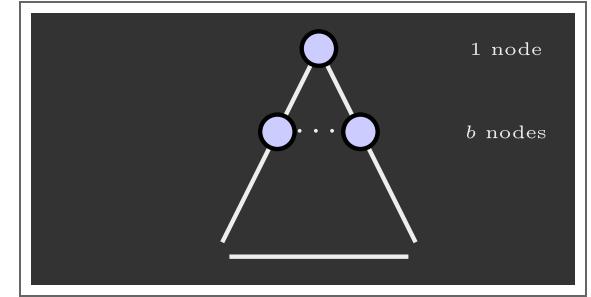
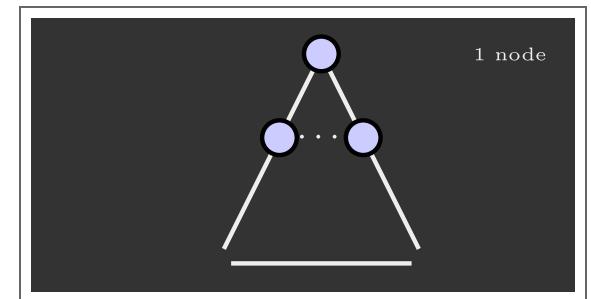
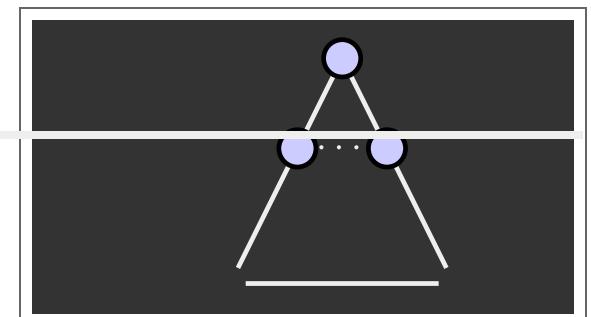
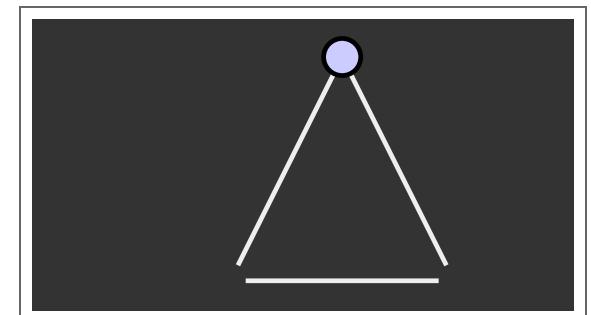
Number of nodes in a tree?

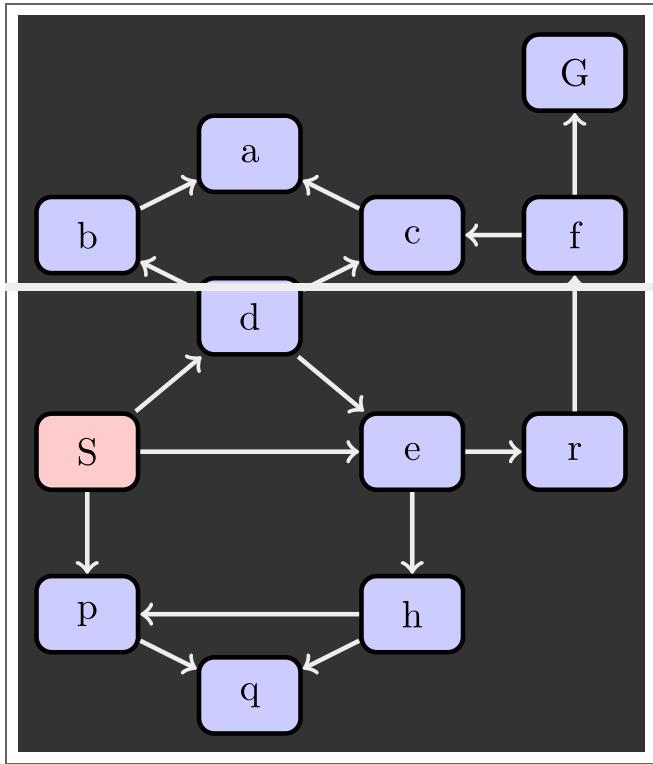
- $1 + b + b^2 + \dots + b^m = \mathcal{O}(b^m)$

State Space Graph

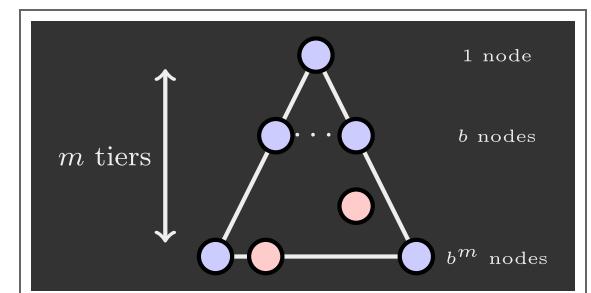
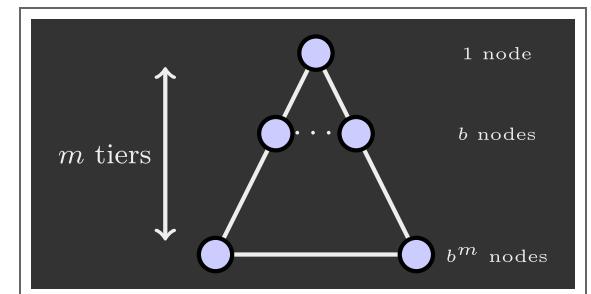
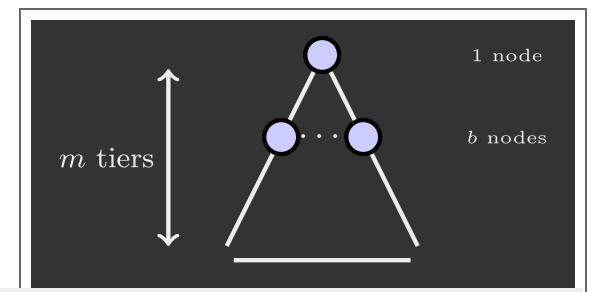


BREADTH-FIRST SEARCH

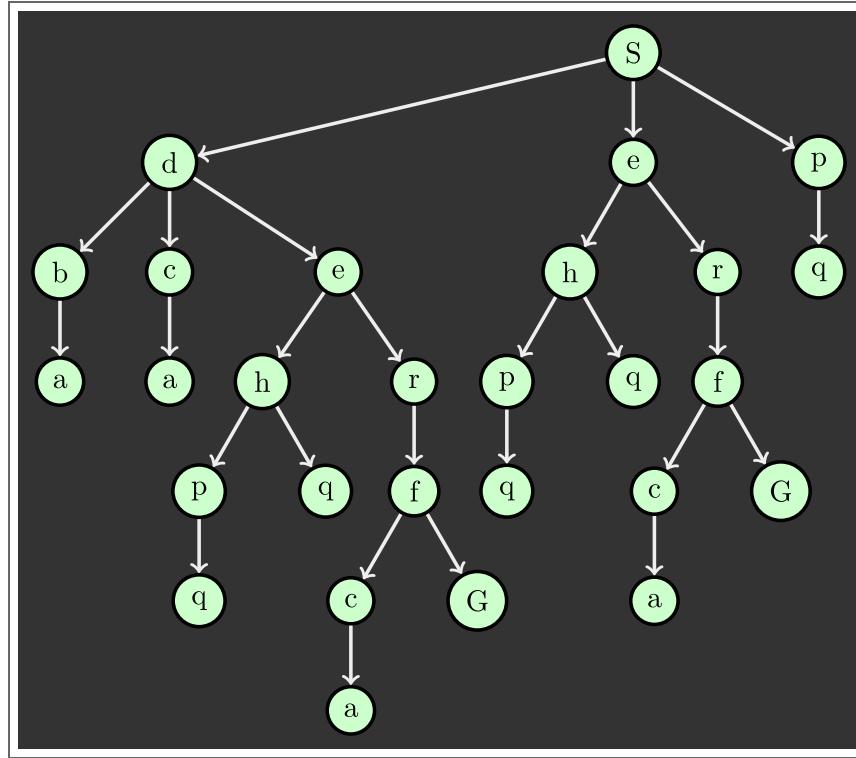
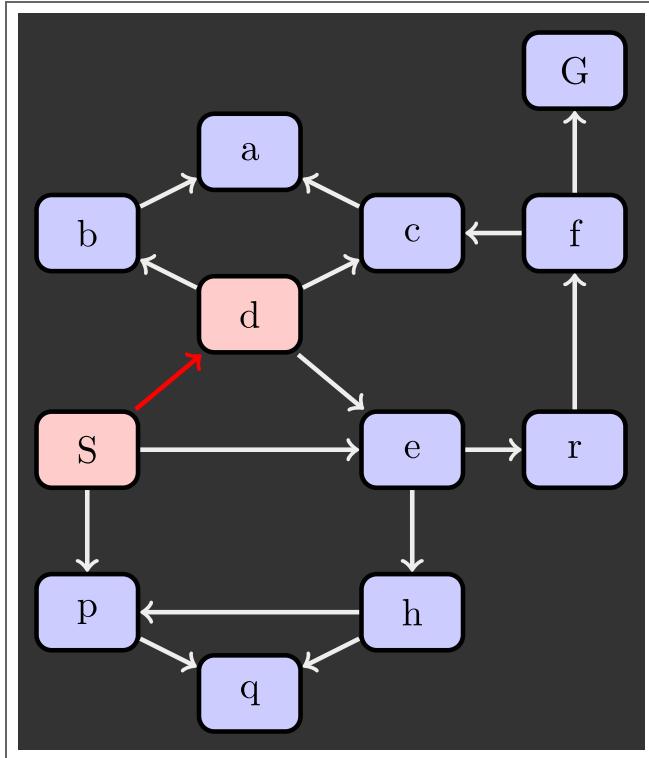


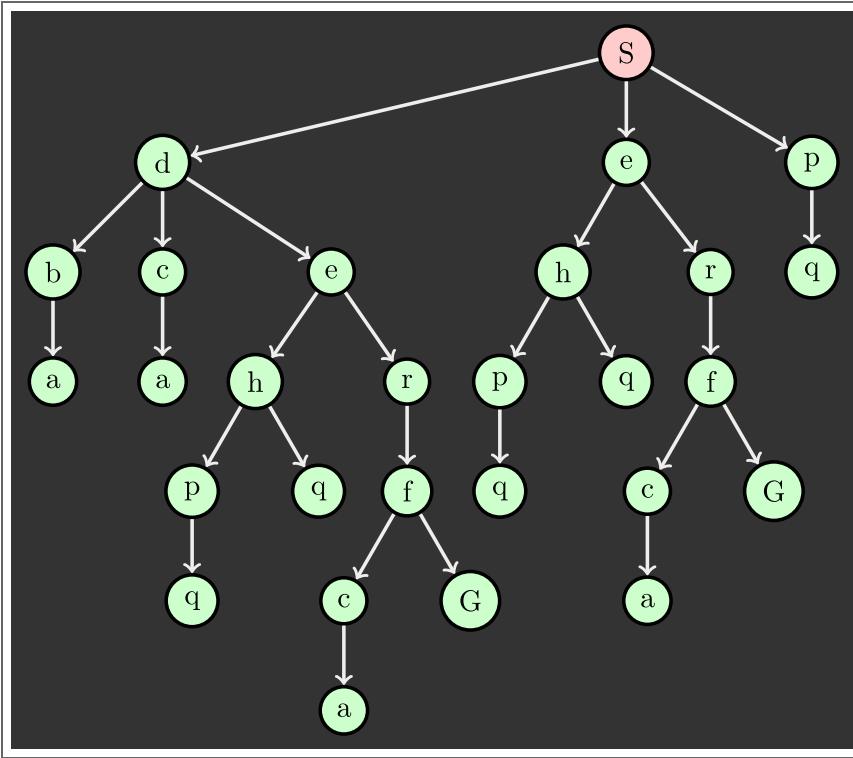
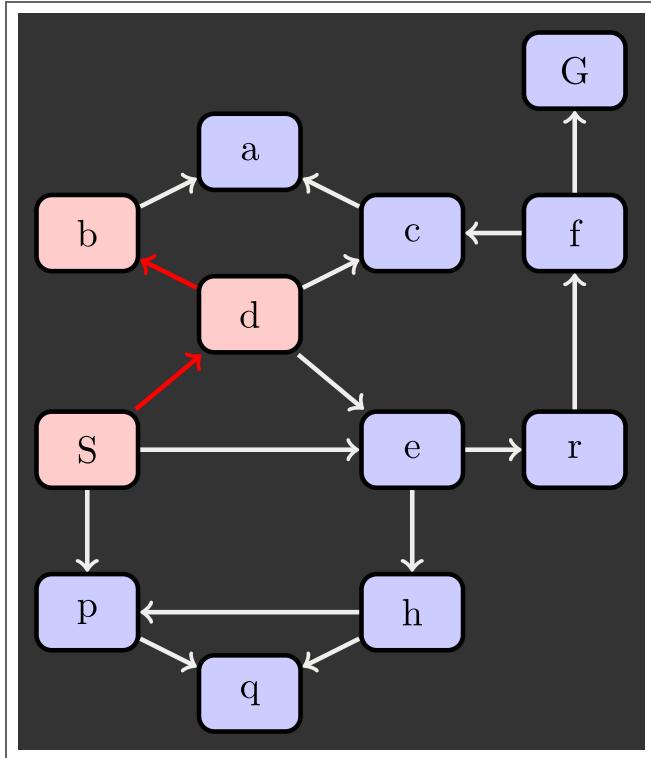


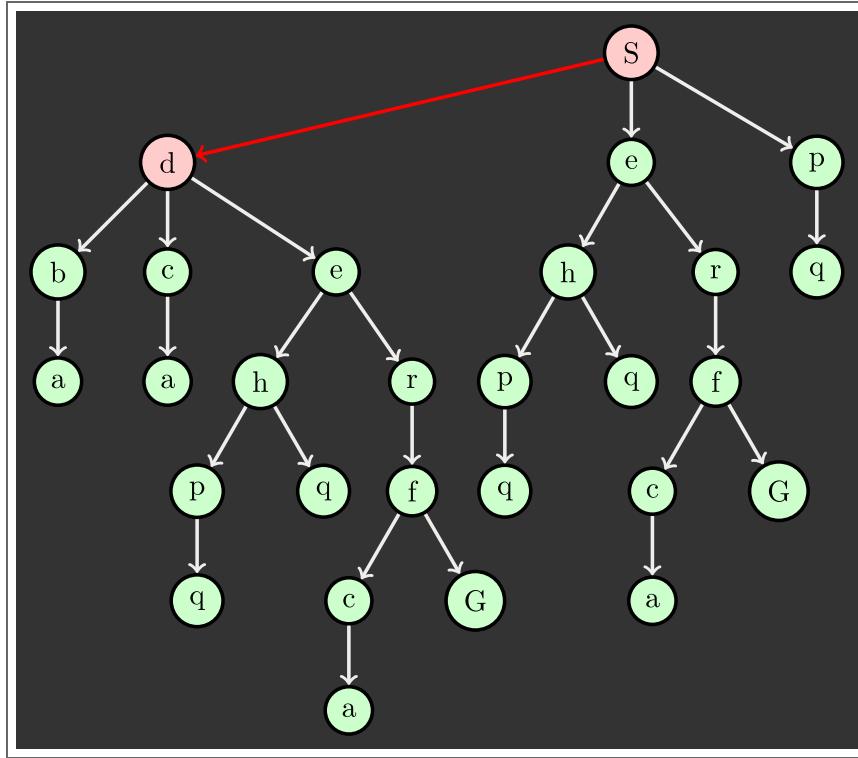
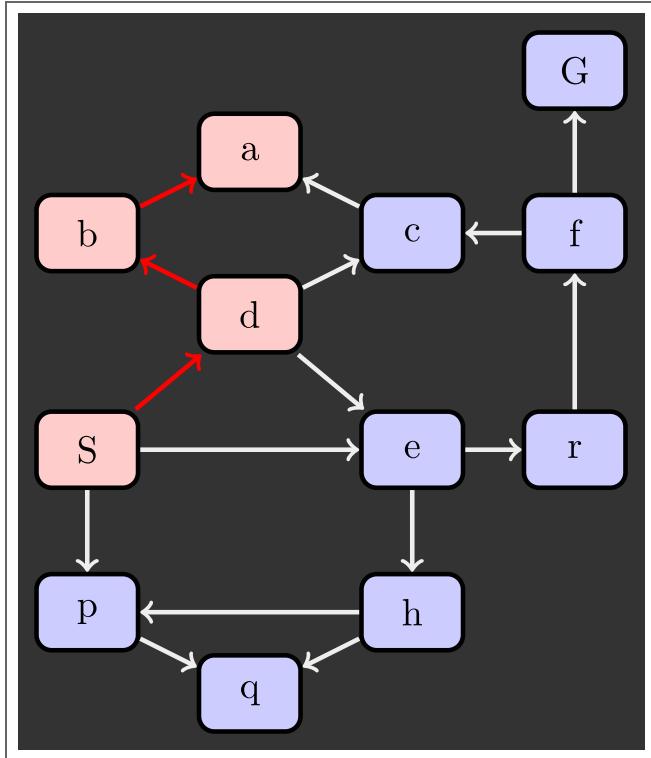
BREADTH FIRST SEARCH

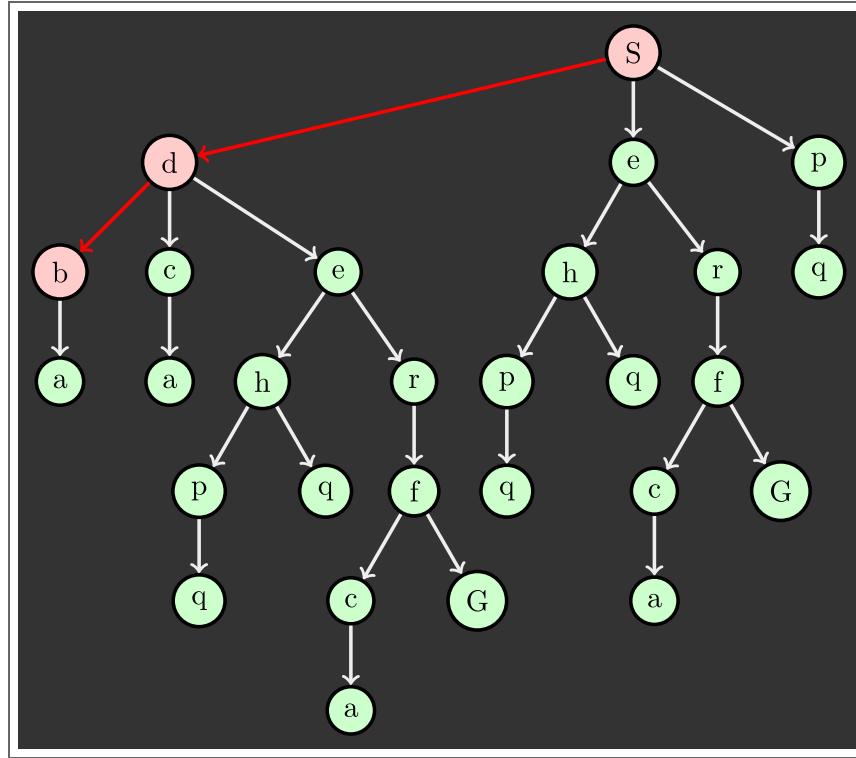
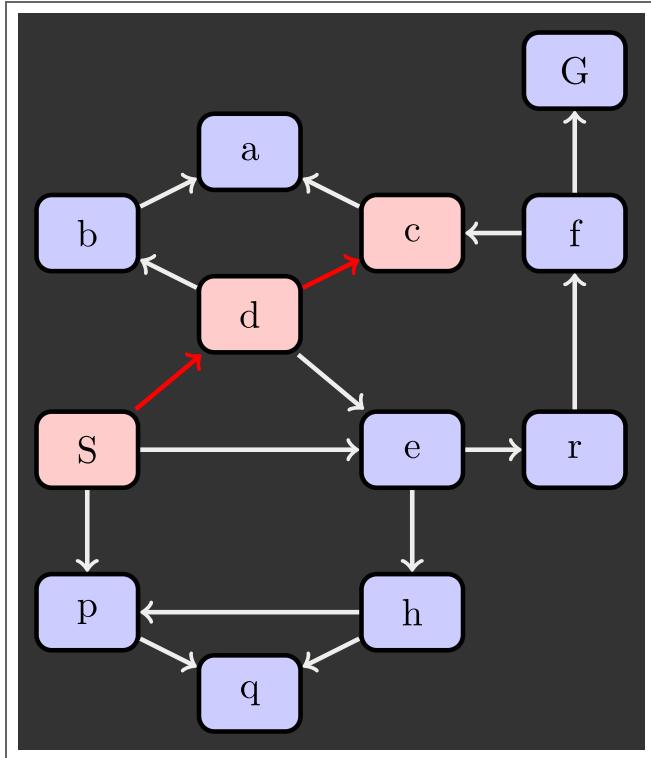


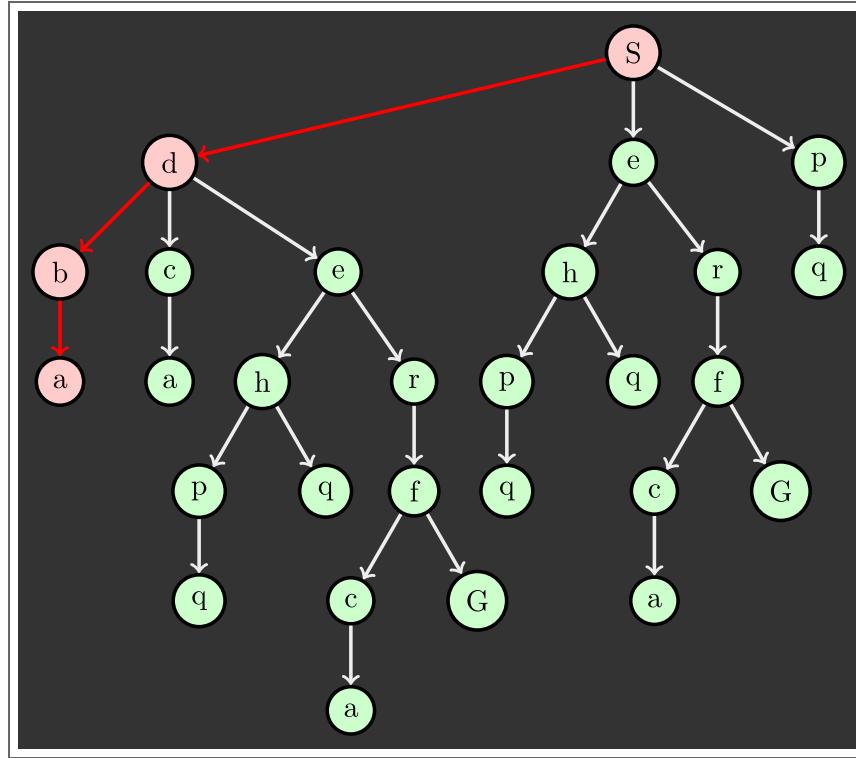
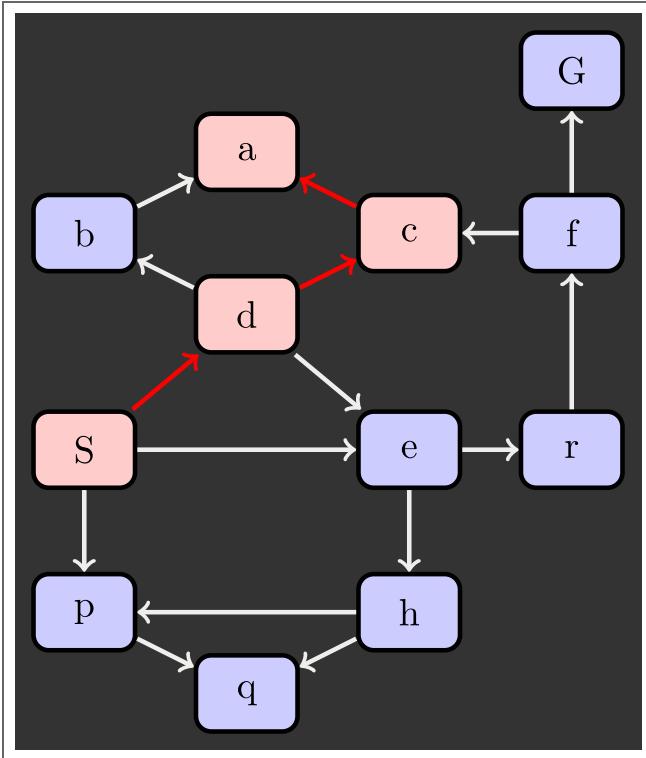
Search Tree

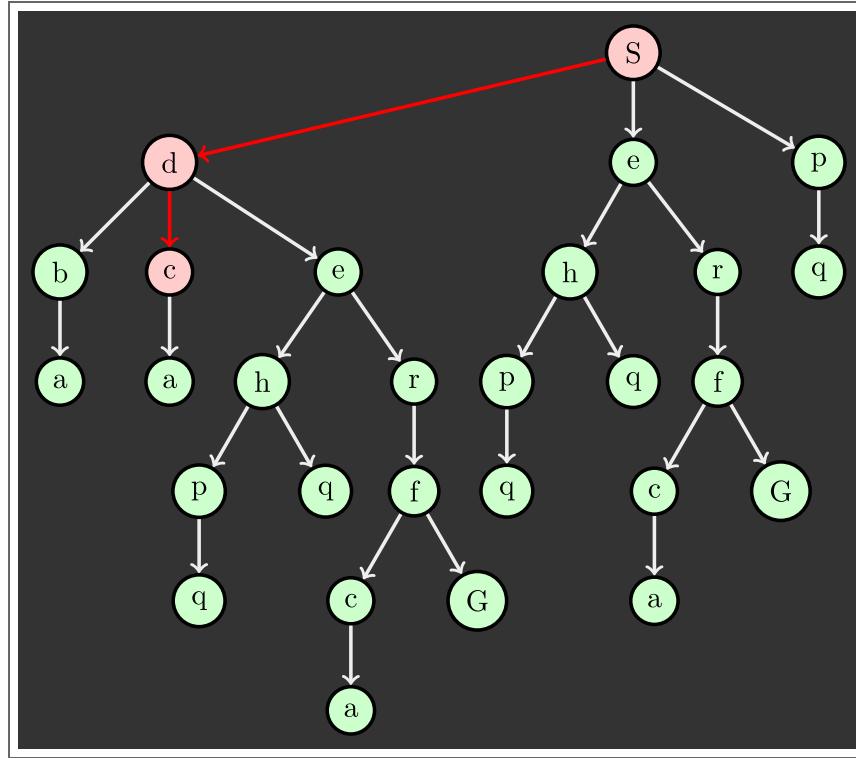
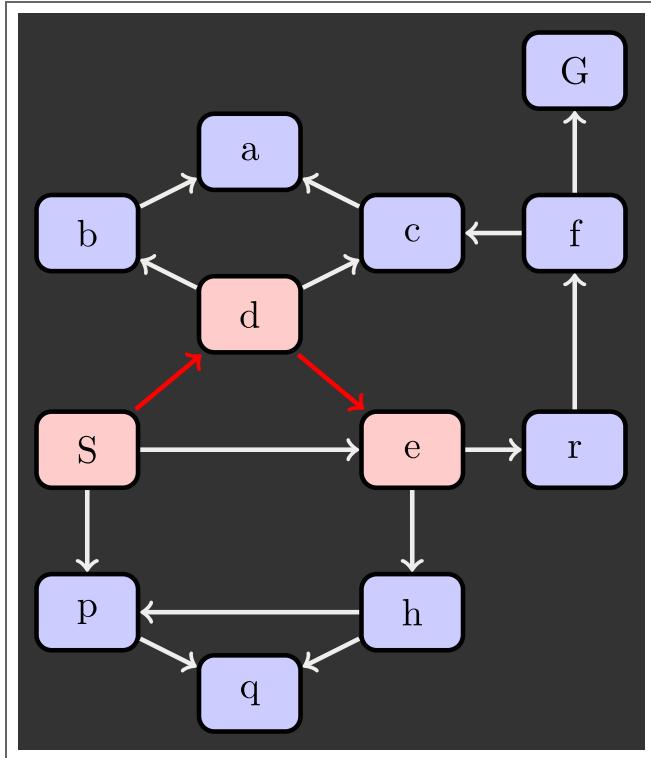


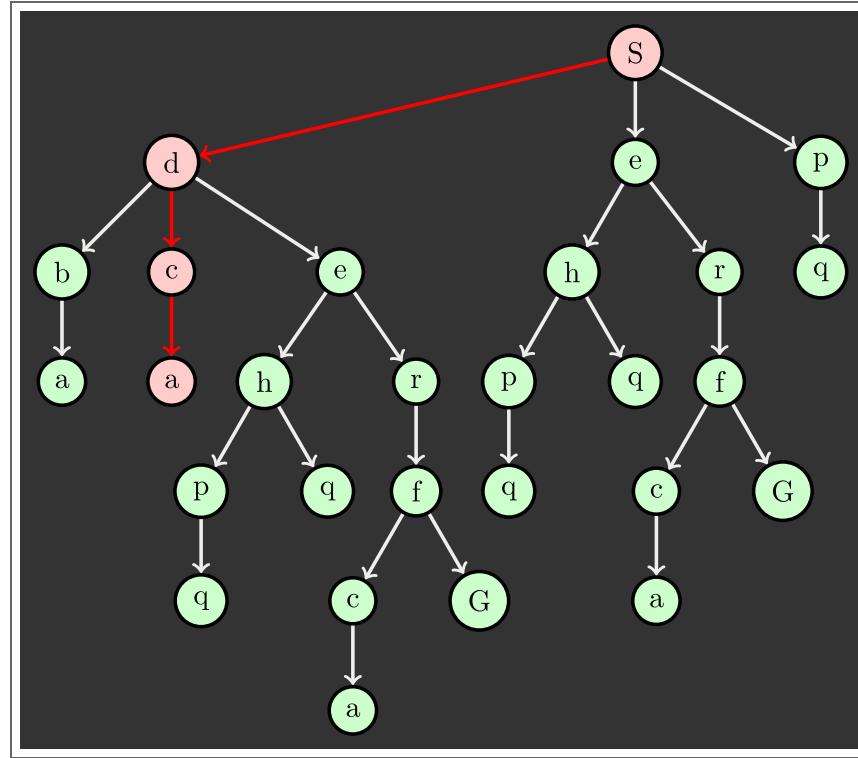
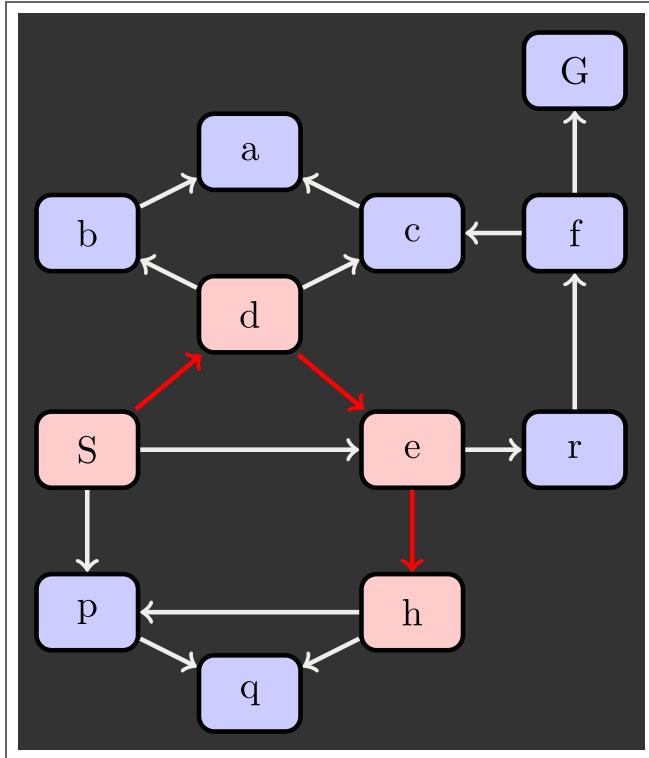


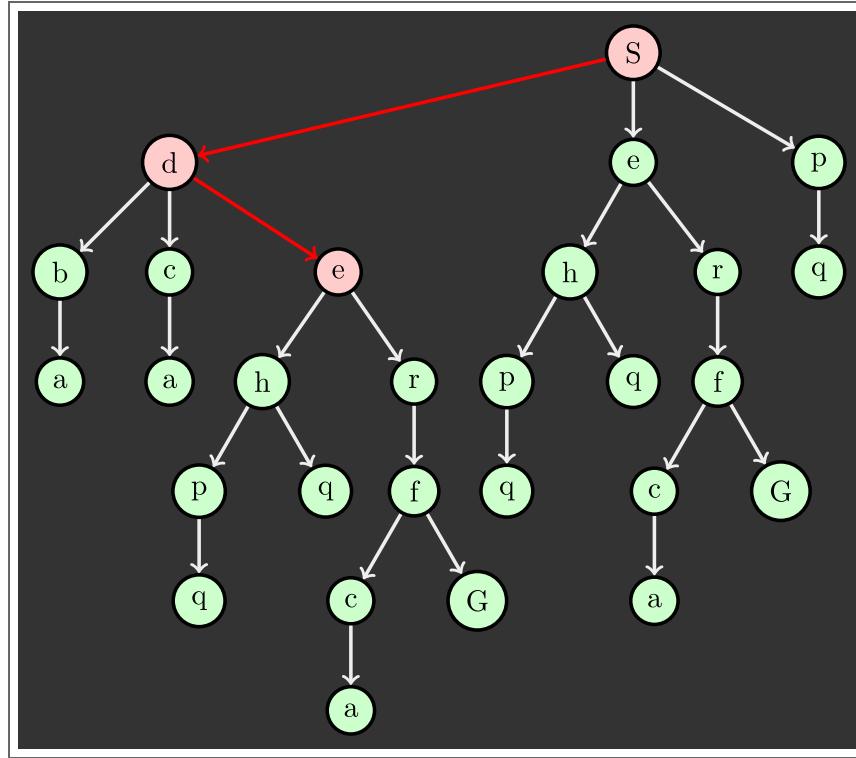
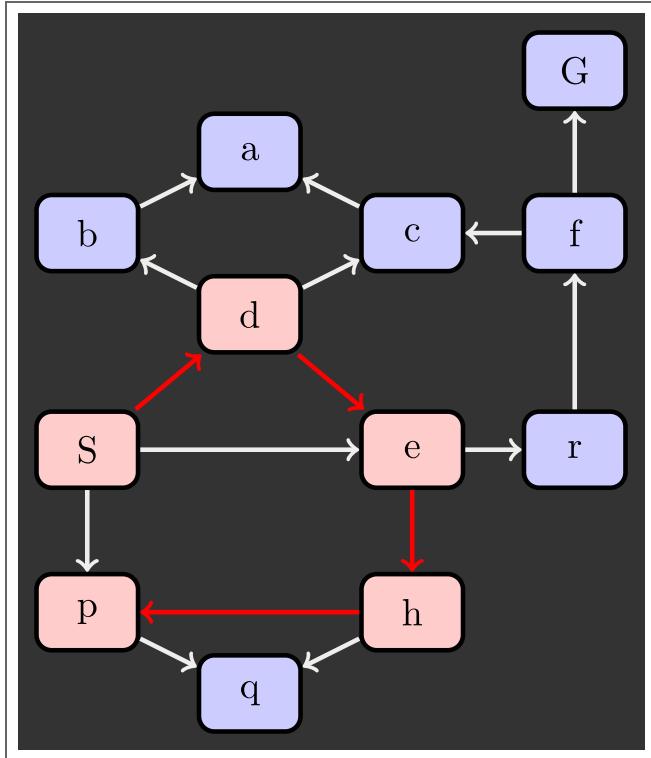


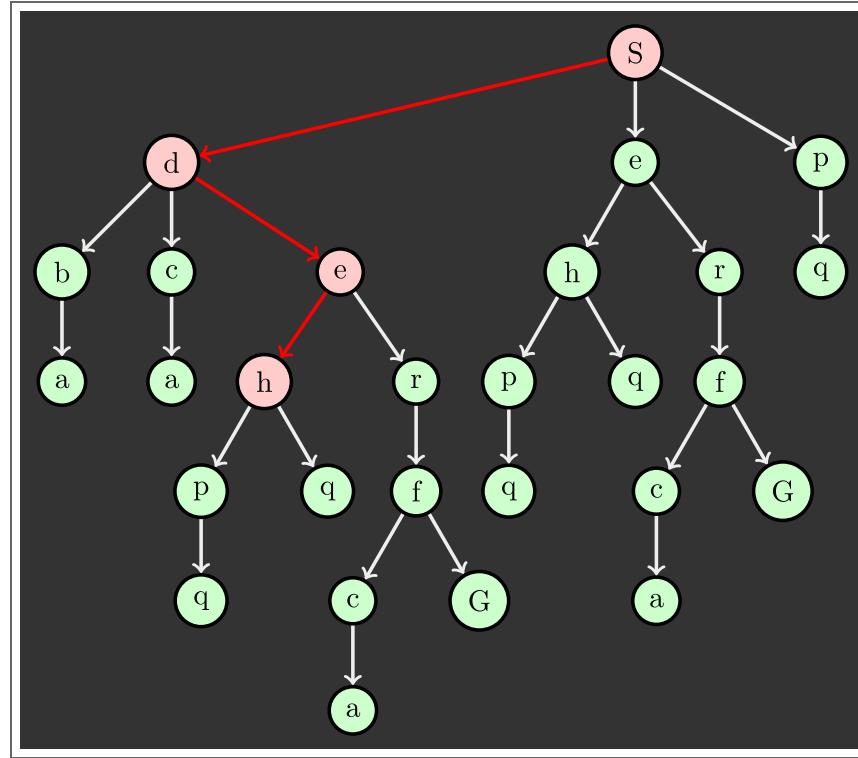
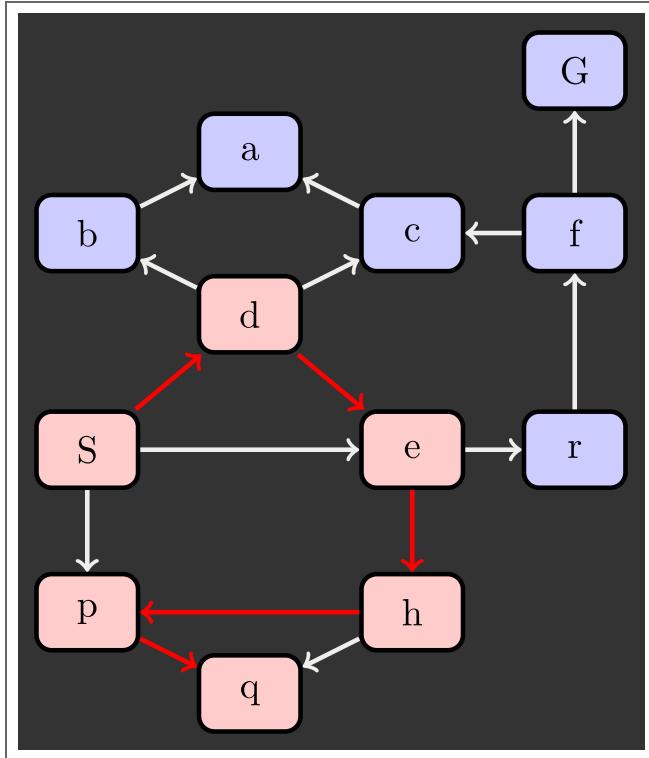


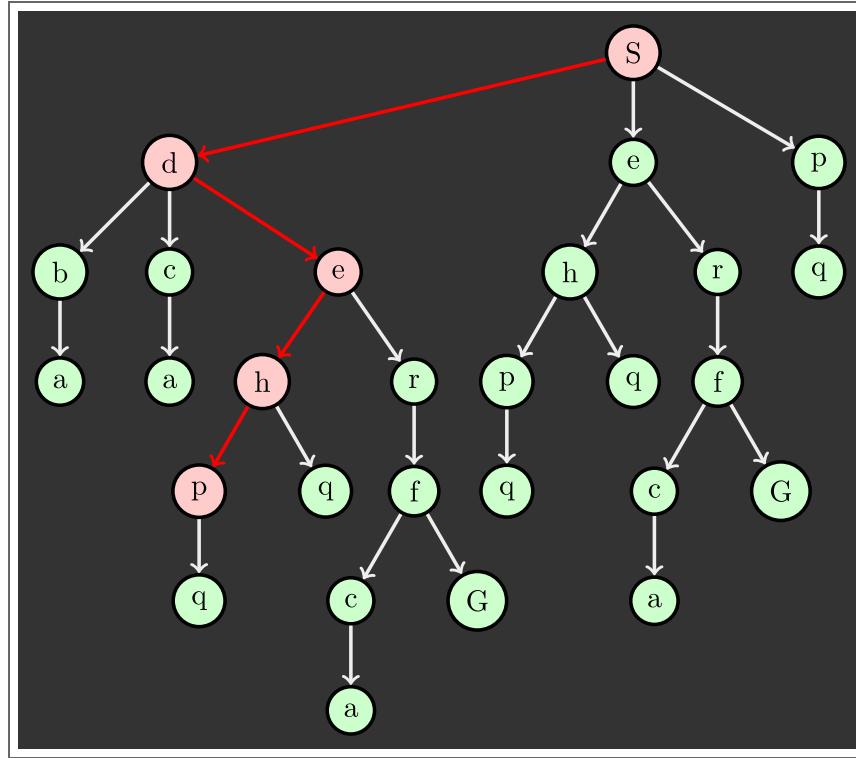
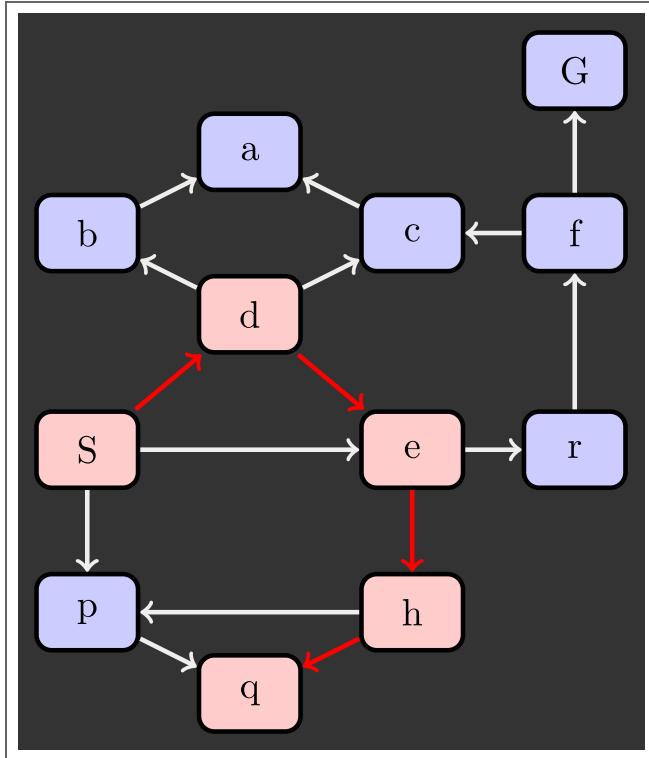


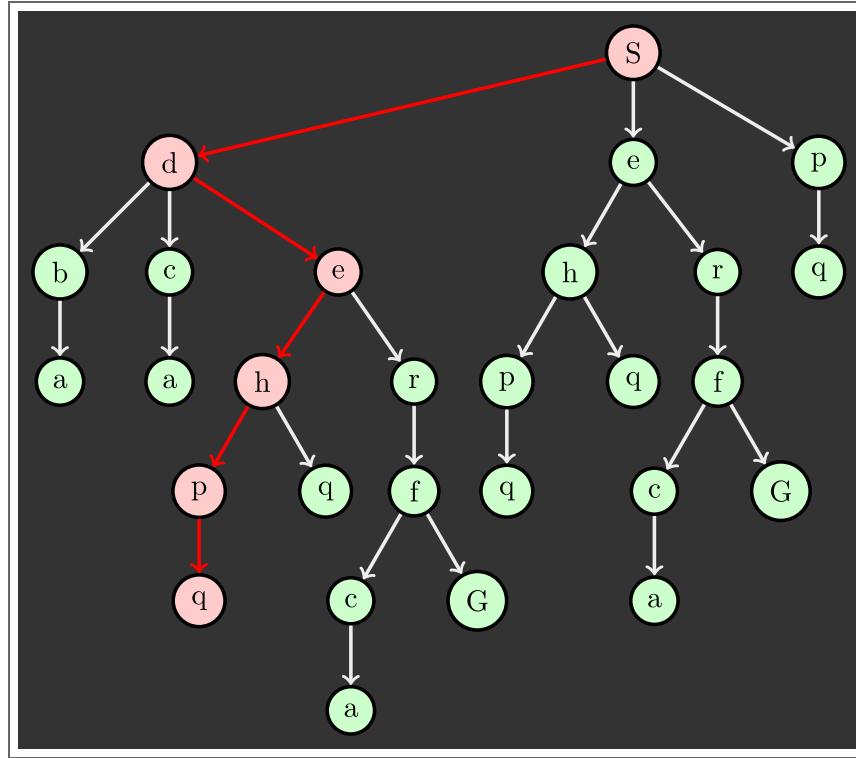
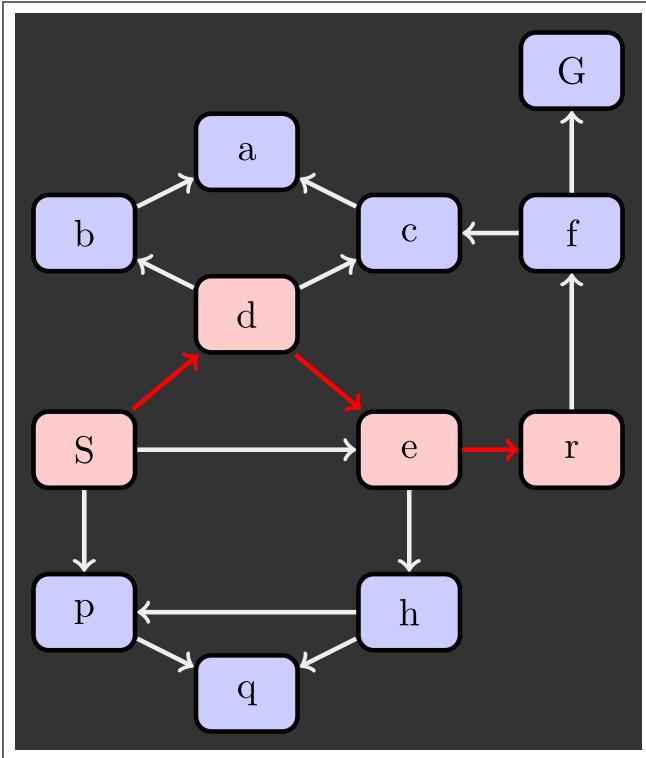


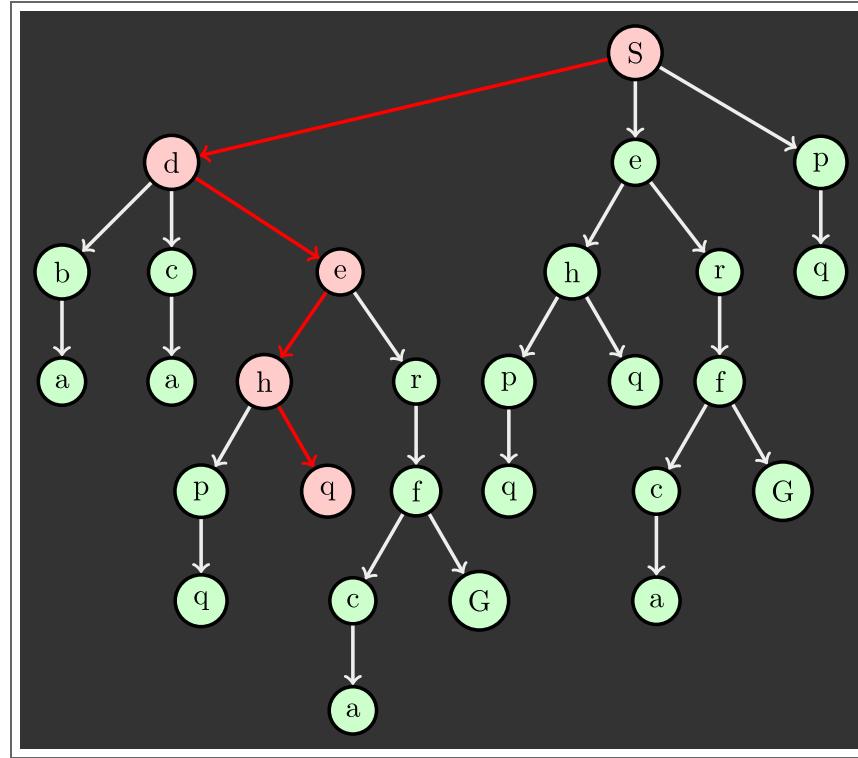
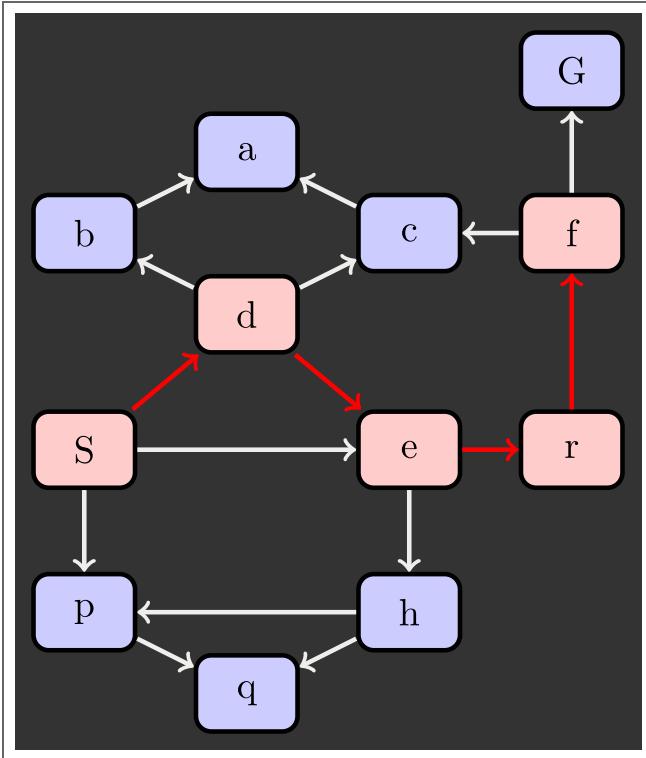


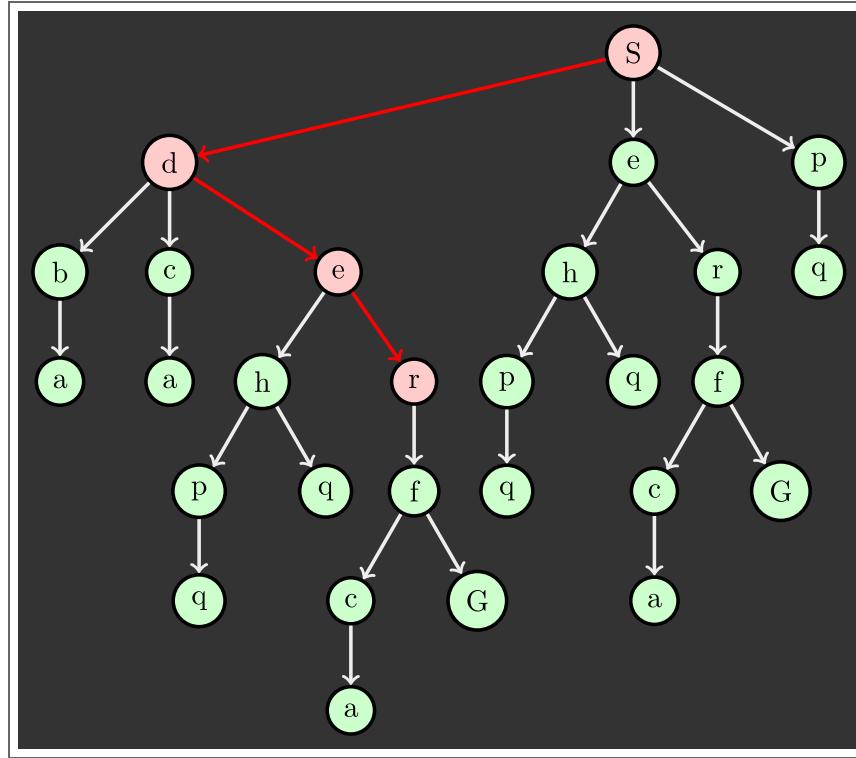
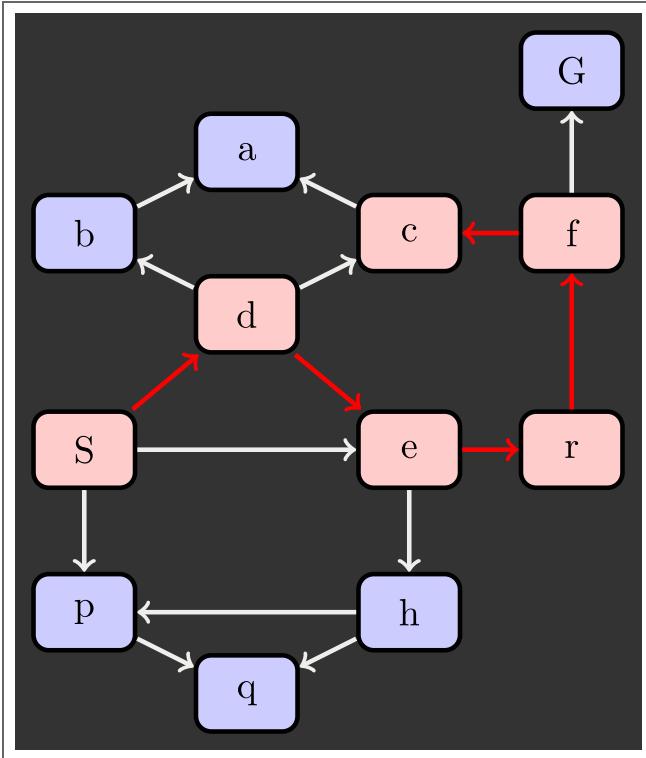


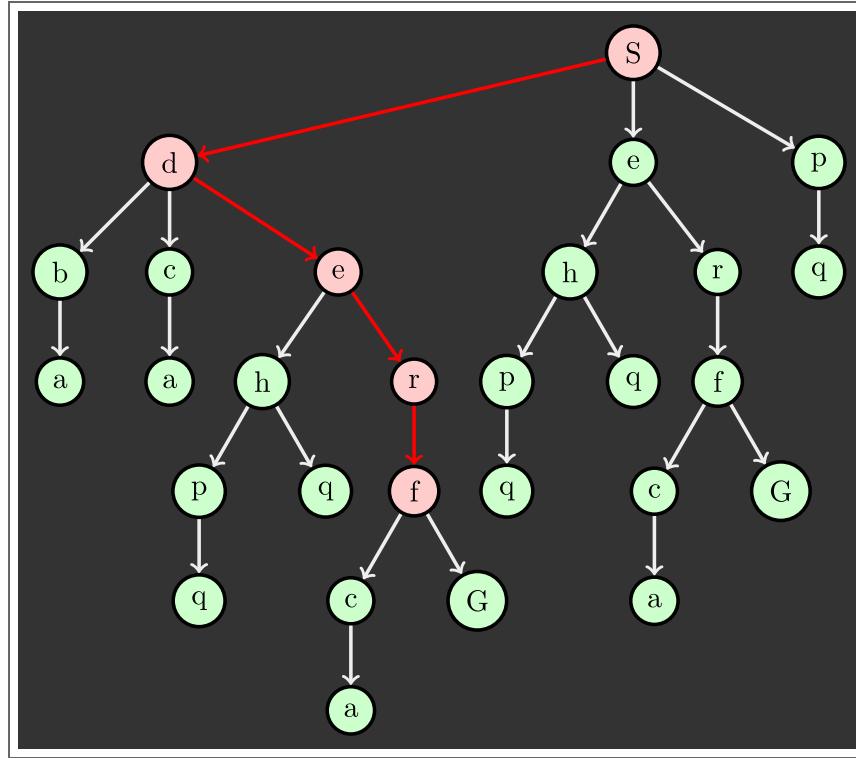
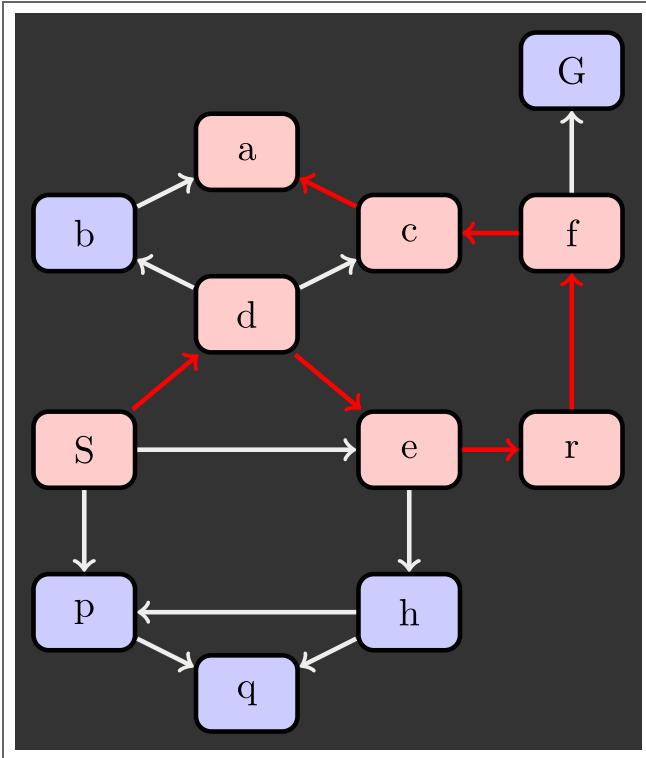


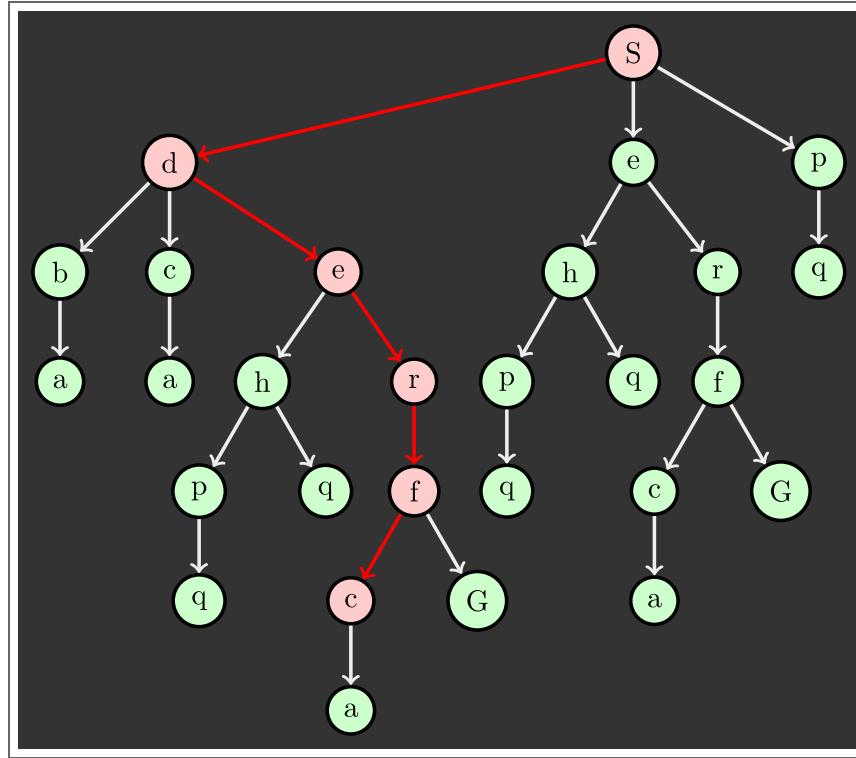
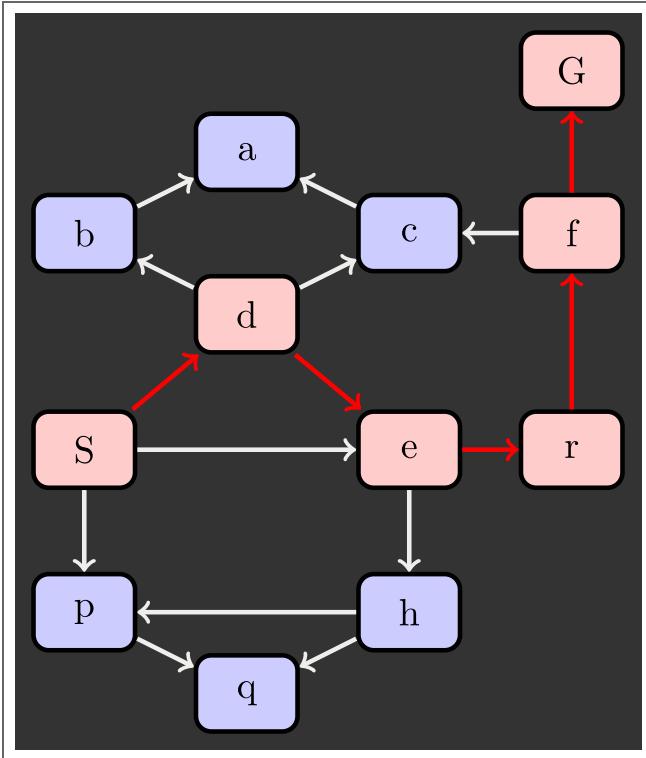


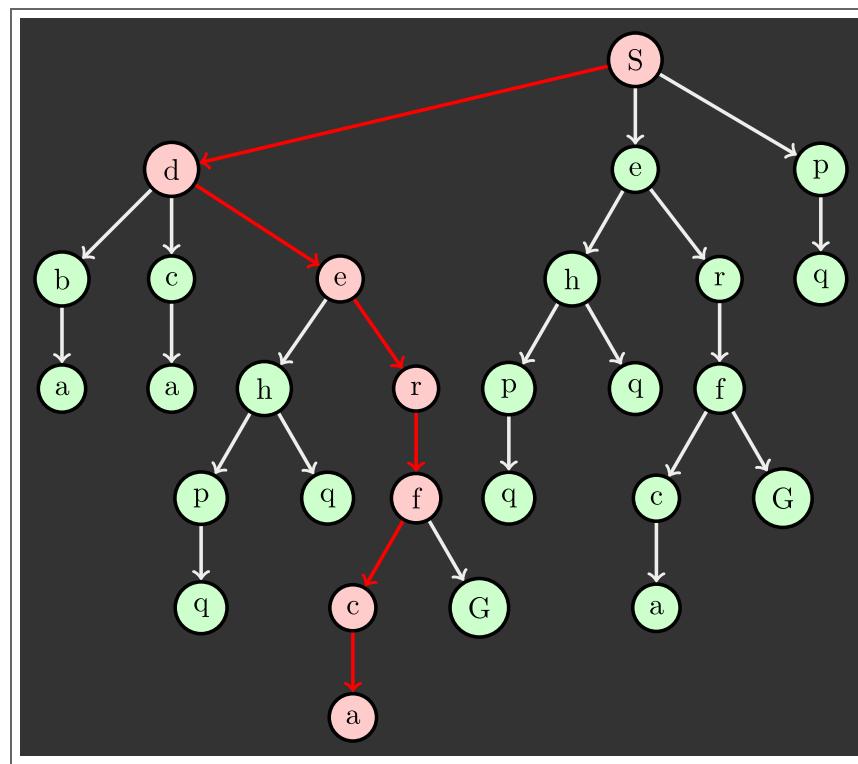


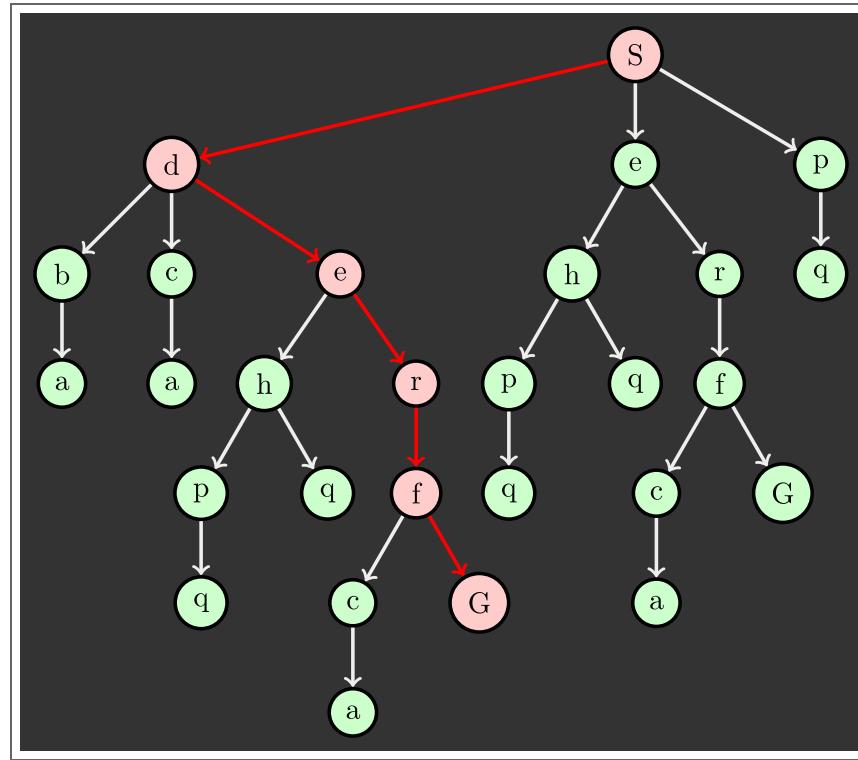










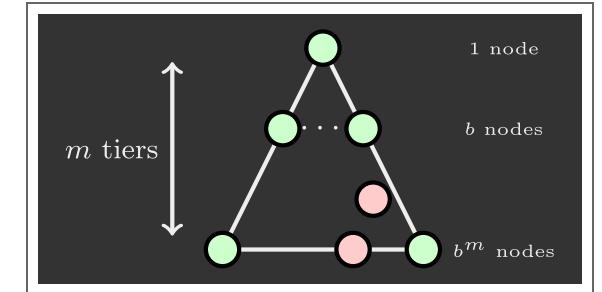


Strategy: expand the deepest node first

Implementation: fringe is a FILO or LIFO stack

What nodes DFS expand?

- Some left prefix of the tree.
- Could process the whole tree!

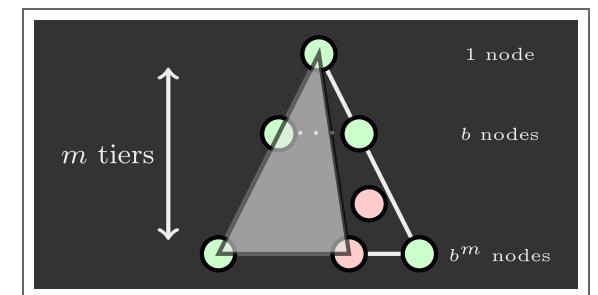
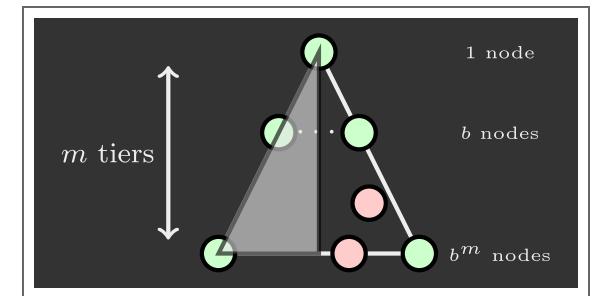
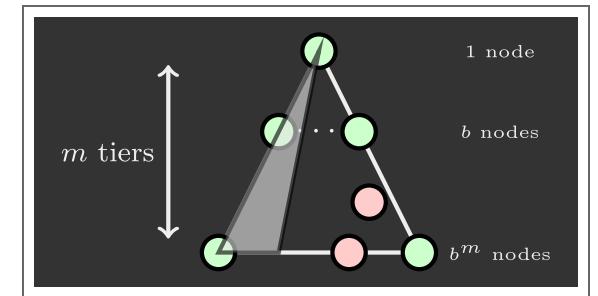


- › If m is finite, takes time $\mathcal{O}(b^m)$

BREADTH-FIRST SEARCH (BFS) PROPERTIES

What nodes BFS expand?

- › Processes all nodes above shallowest solution
- › Let depth of shallowest solution be s
- › Search takes time $\mathcal{O}(b^s)$



Is it complete?

- › m could be infinite, so only if we prevent cycles (more later)

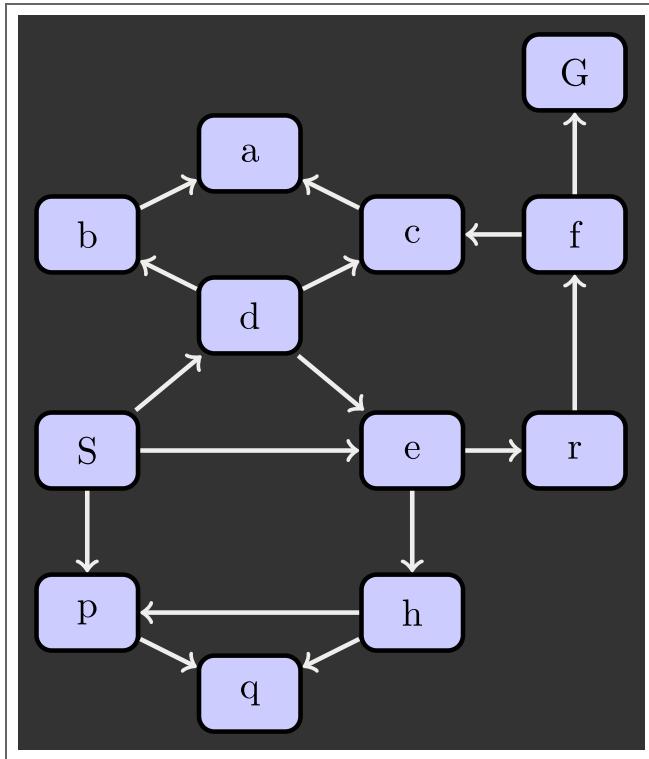
How much space does the fringe take?

- › Only has siblings on path to root, so $\mathcal{O}(bm)$.

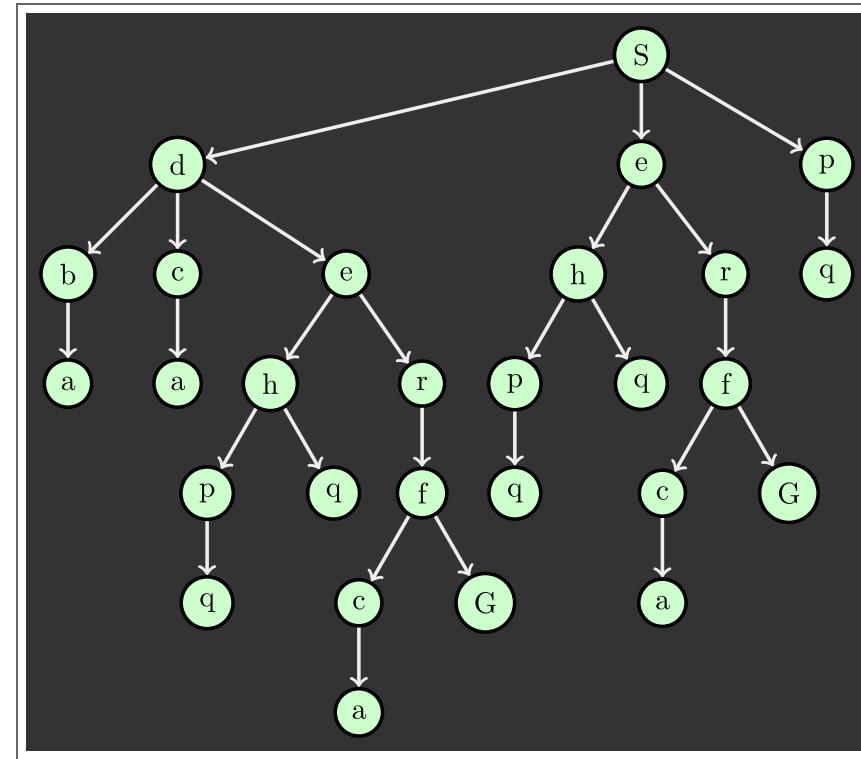
Is it optimal?

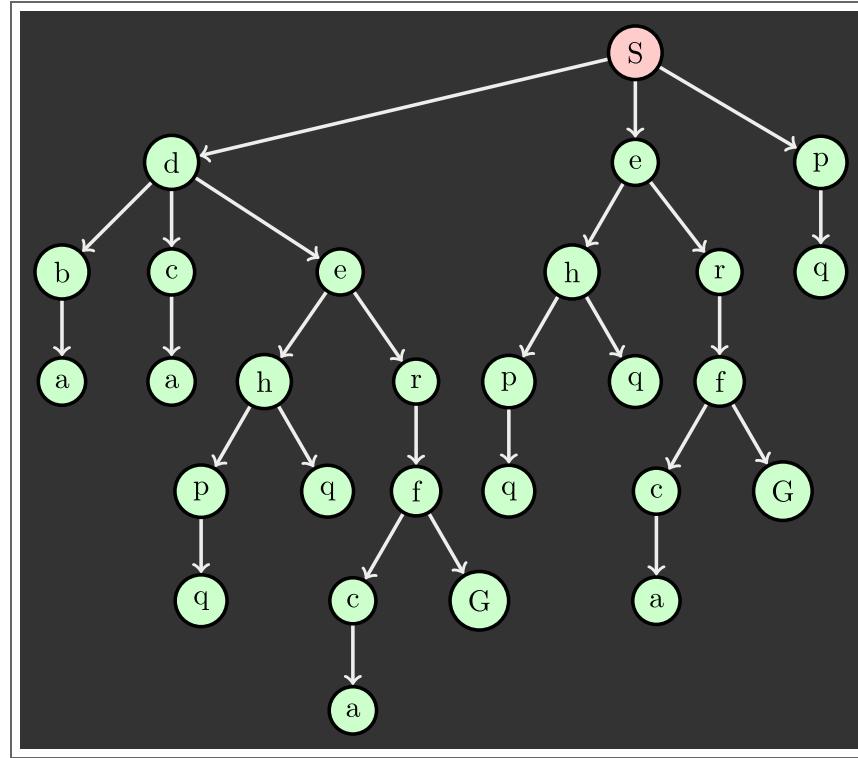
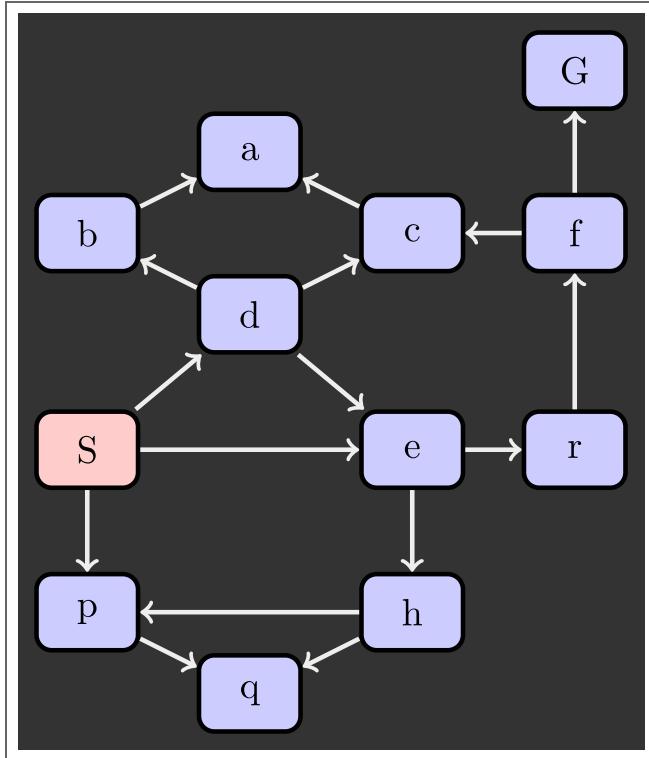
- No, it finds the “leftmost” solution, regardless of depth or cost.

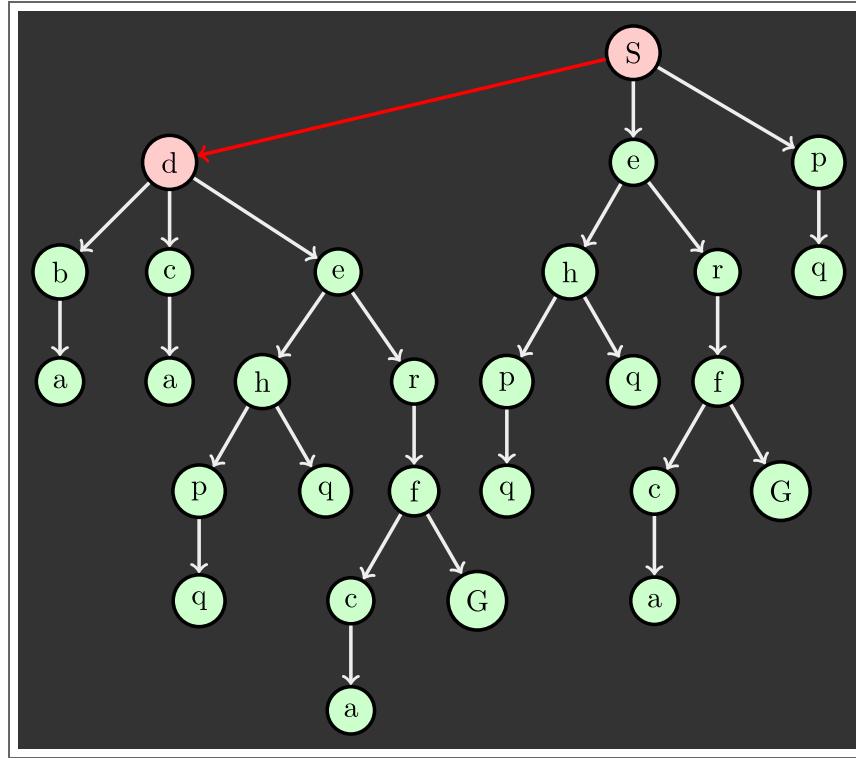
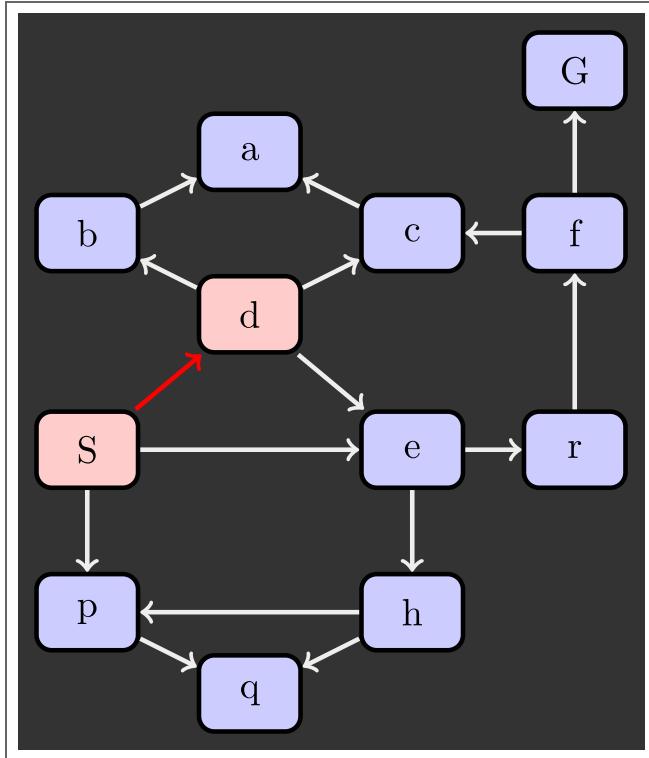
State Space Graph

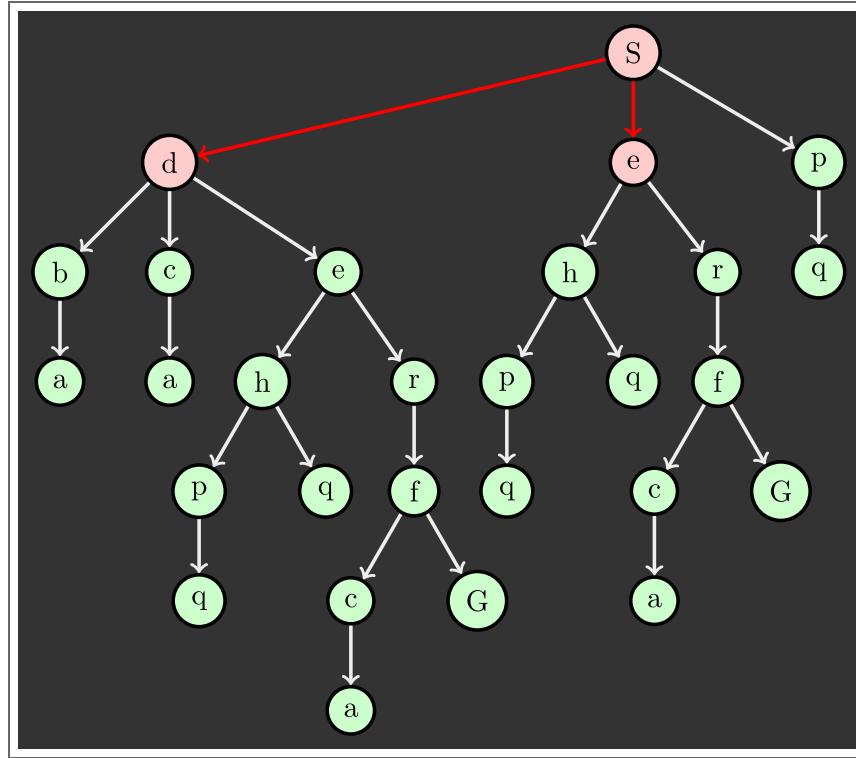
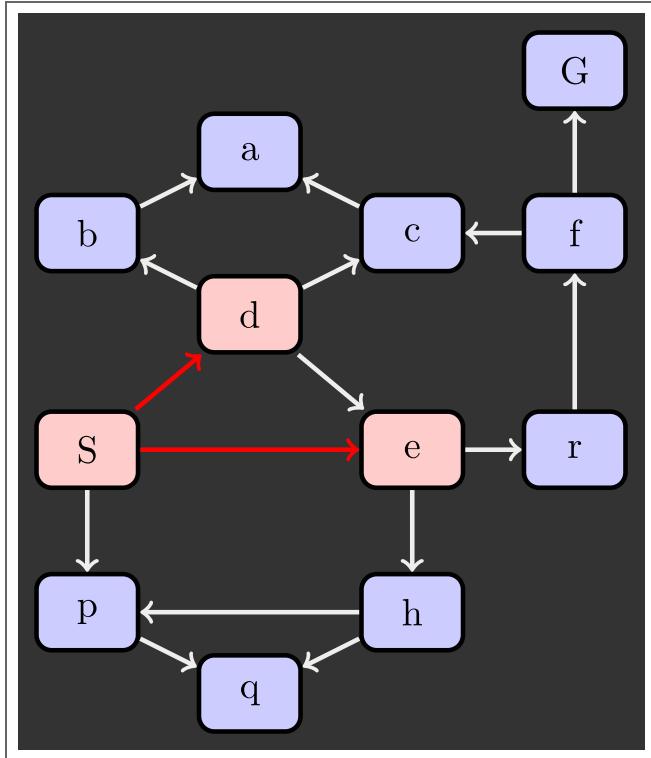


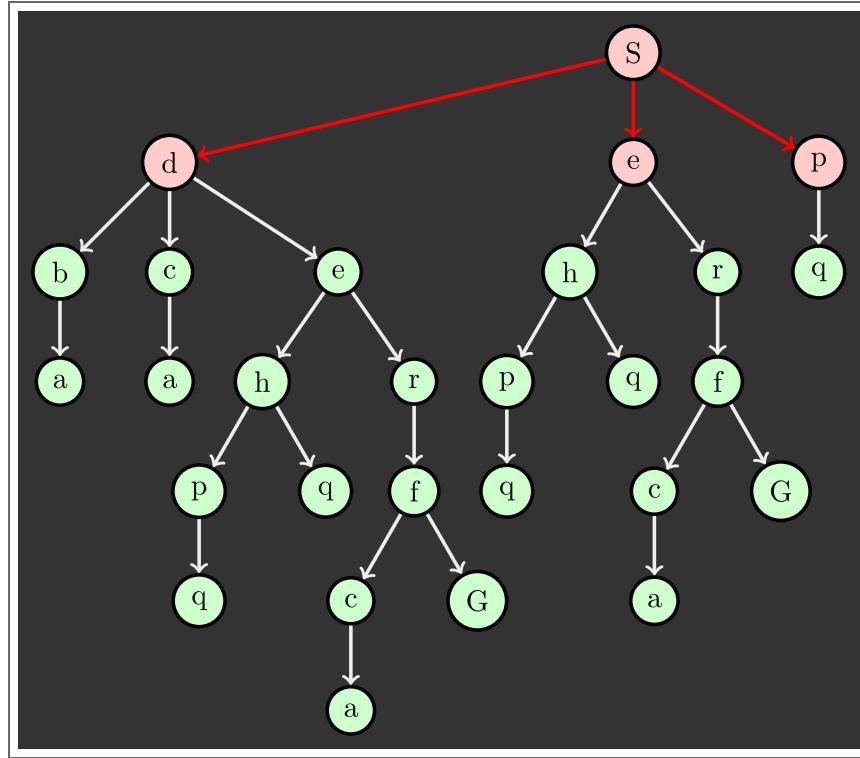
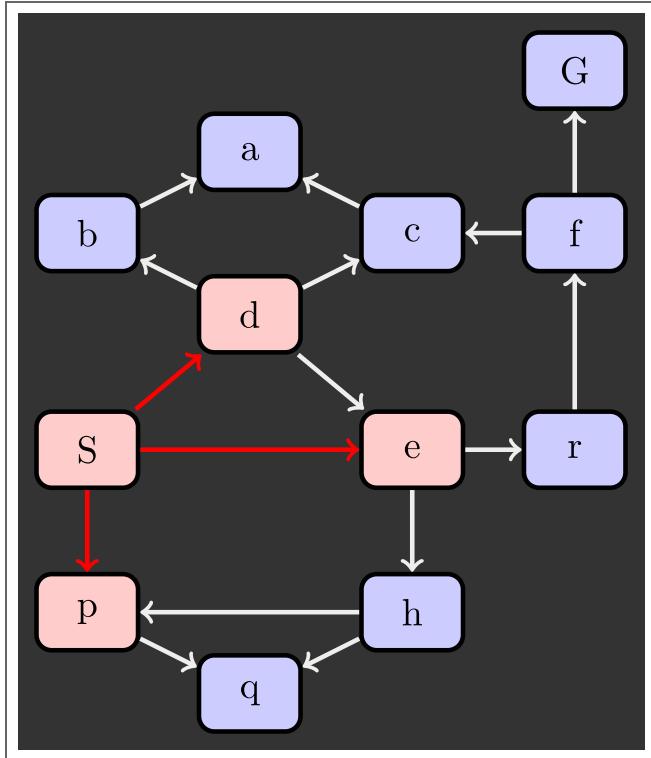
Search Tree

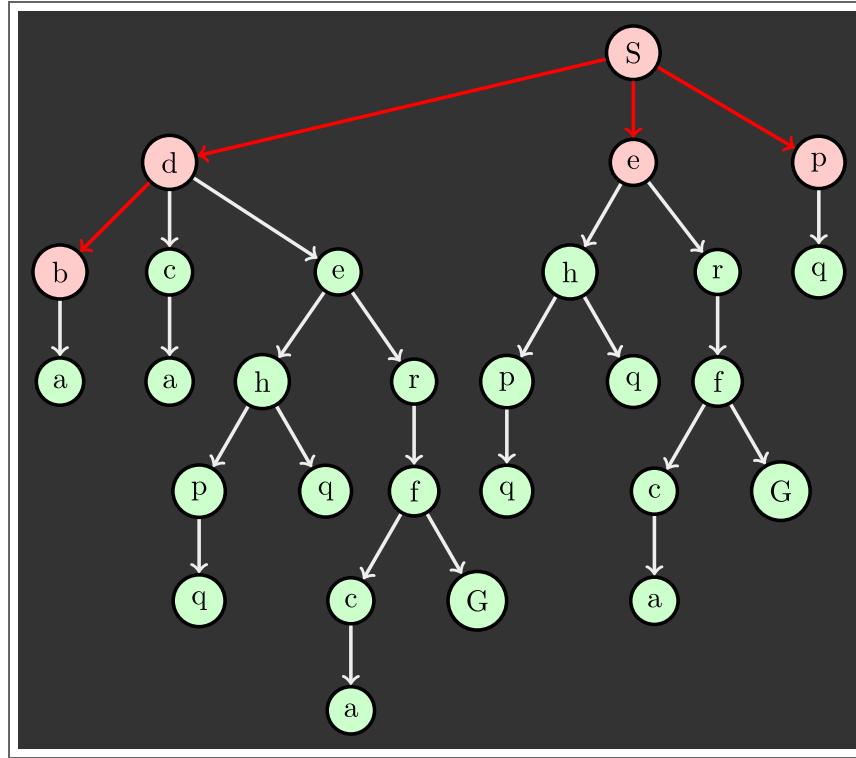
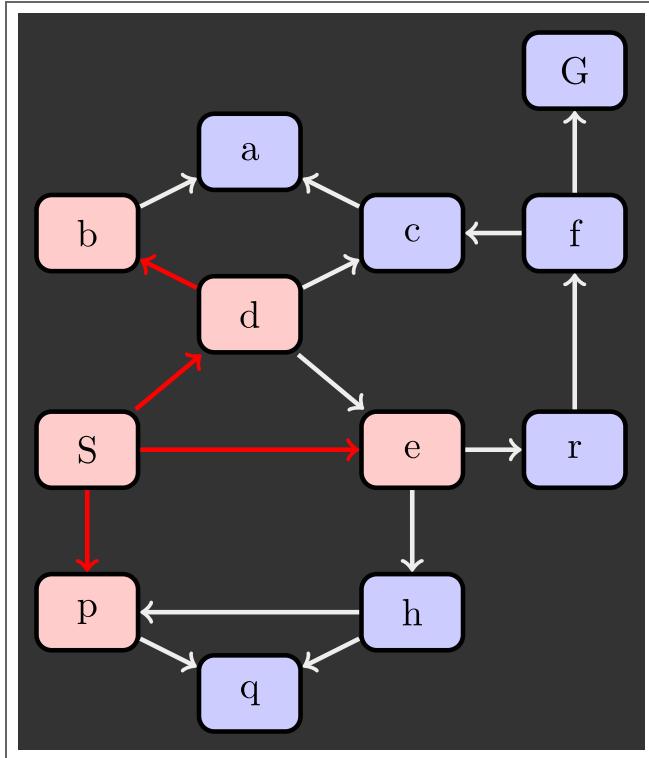


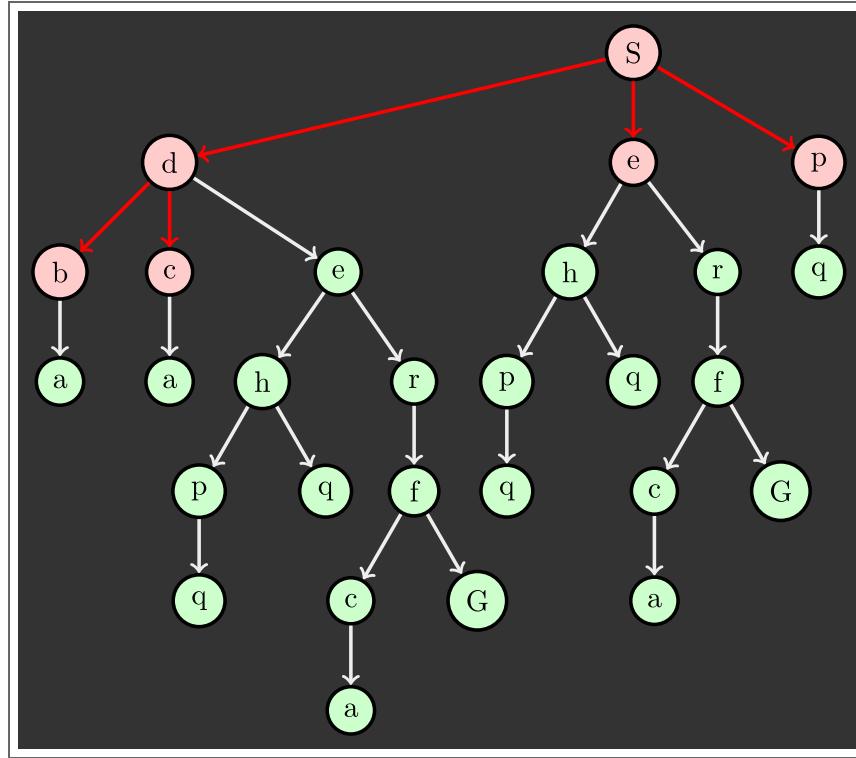
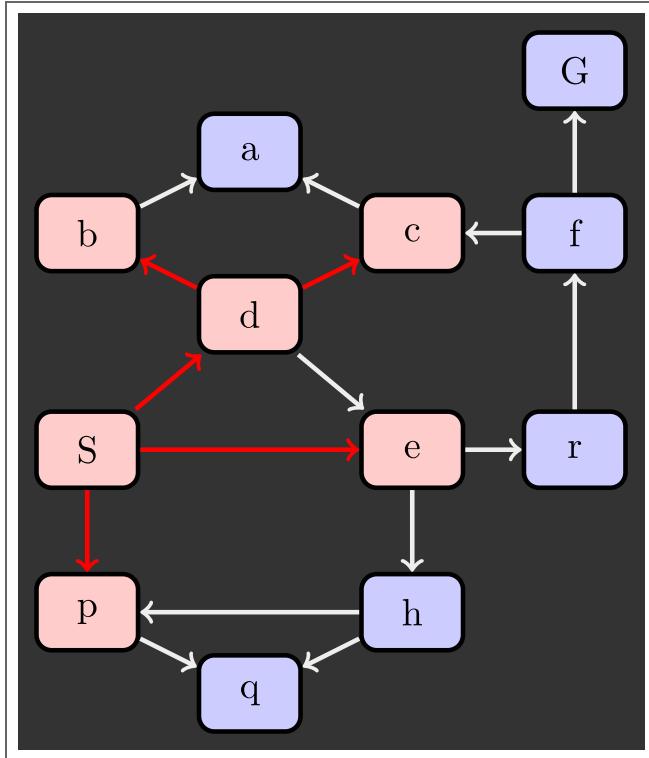


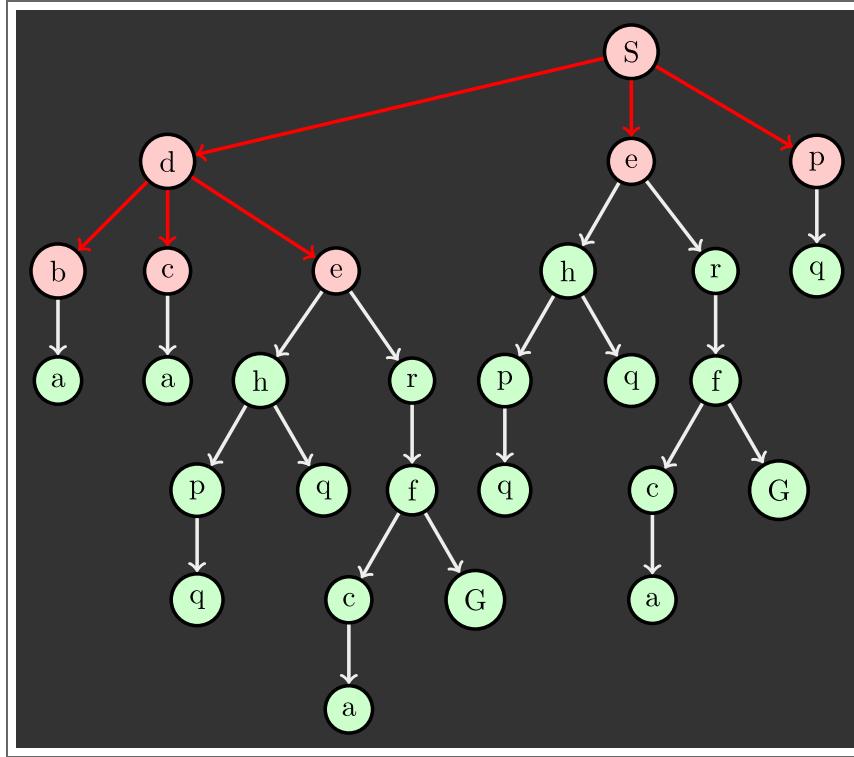
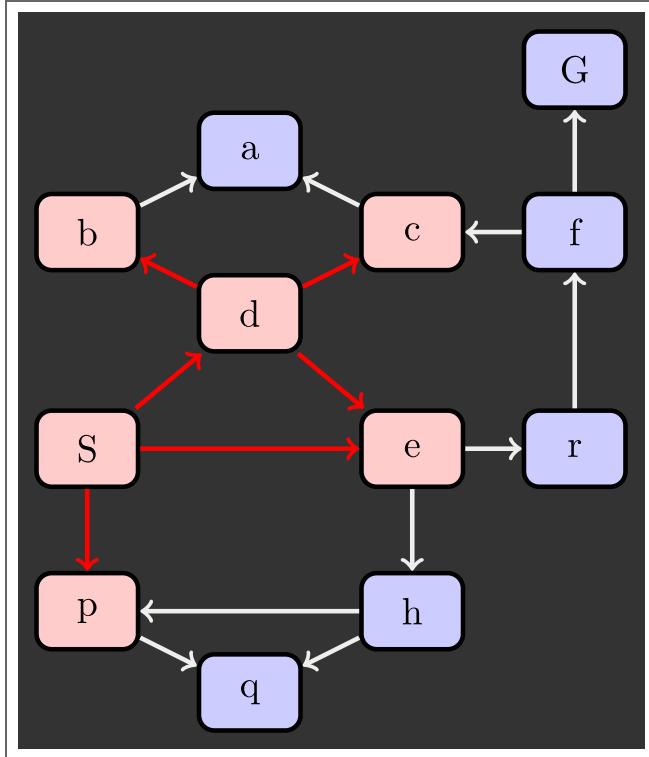












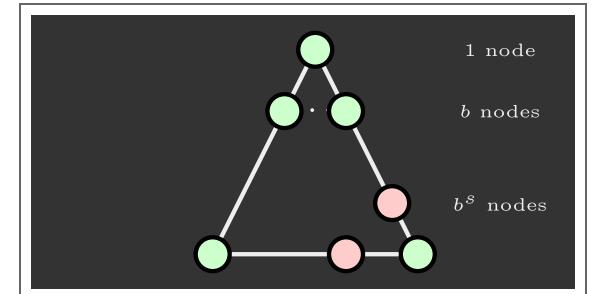
Strategy: expand the shallowest node first

Implementation: fringe is a FIFO queue

How much space does the fringe take?

- Roughly the last tier, so $\mathcal{O}(b^s)$.

Is it complete?



- › s must be finite if a solution exists, so yes!

Is it optimal?

- › Only if costs are all 1 (more on costs later)

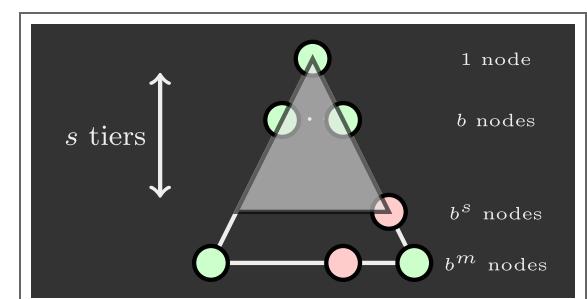
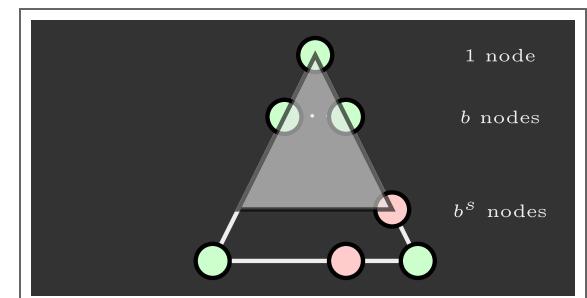
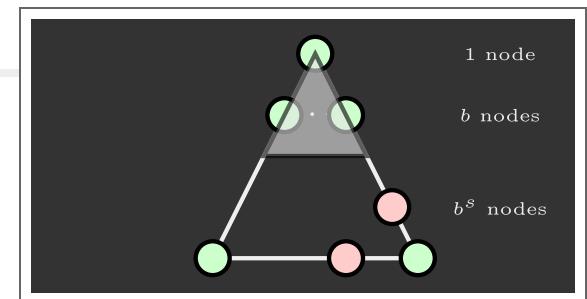
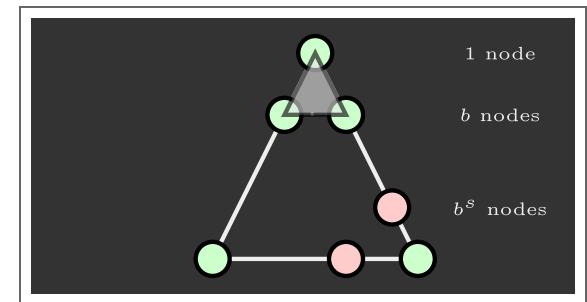
ITERATIVE DEEPENING

Idea: get the space advantage of DFS with the time / shallow-solution advantage of BFS.

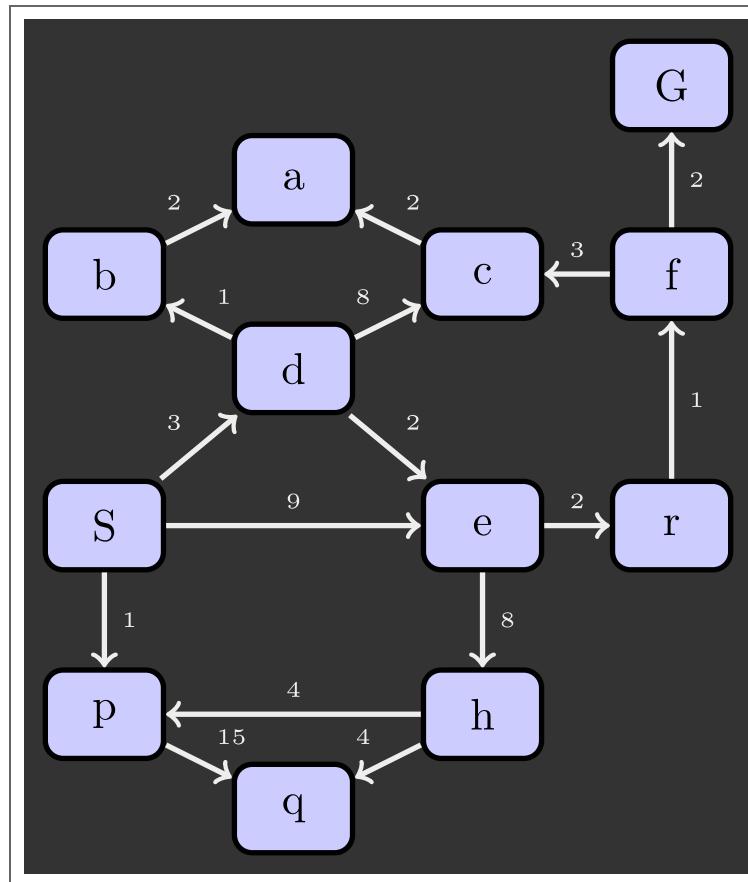
- › Run a DFS with depth limit 1. If no solution ...
- › Run a DFS with depth limit 2. If no solution ...
- › Run a DFS with depth limit 3. If no solution ...

Is this not wastefully redundant?

- › Generally most work happens in the deepest level searched, so it is not so bad.



COST SENSITIVE SEARCH

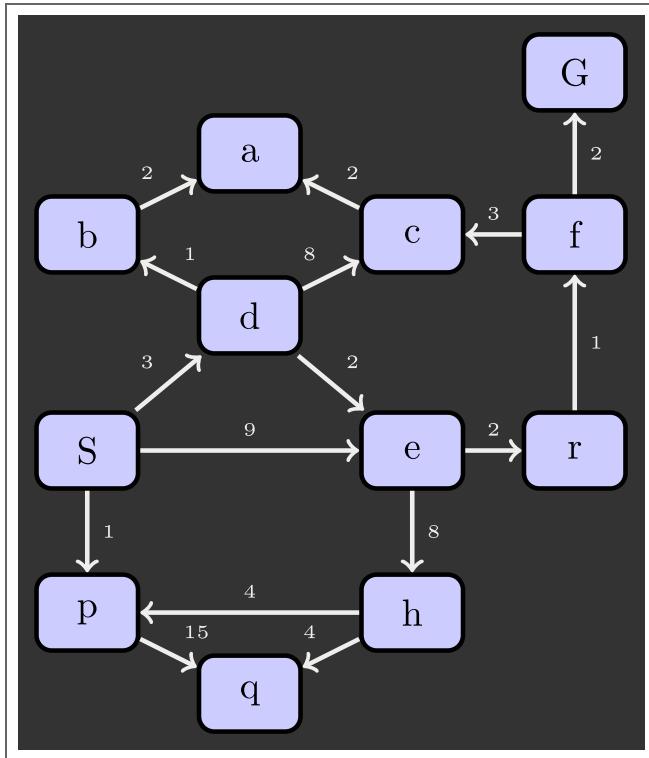


BFS finds the shortest path in terms of number of actions. It does not find the least-cost path. We will now cover a similar algorithm which does find the least-cost path.

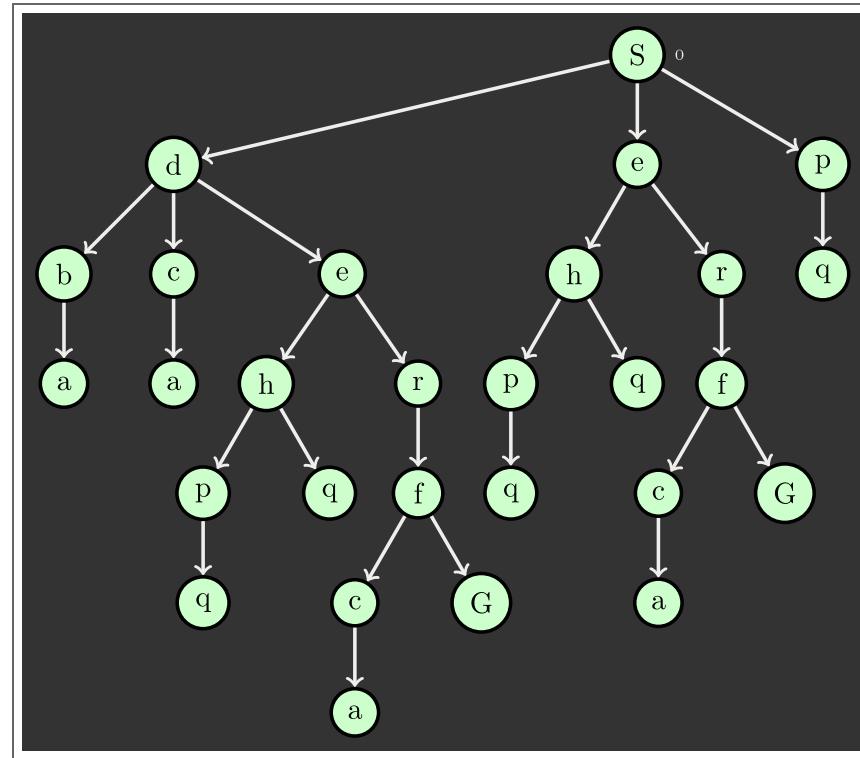
UNIFORM COST SEARCH

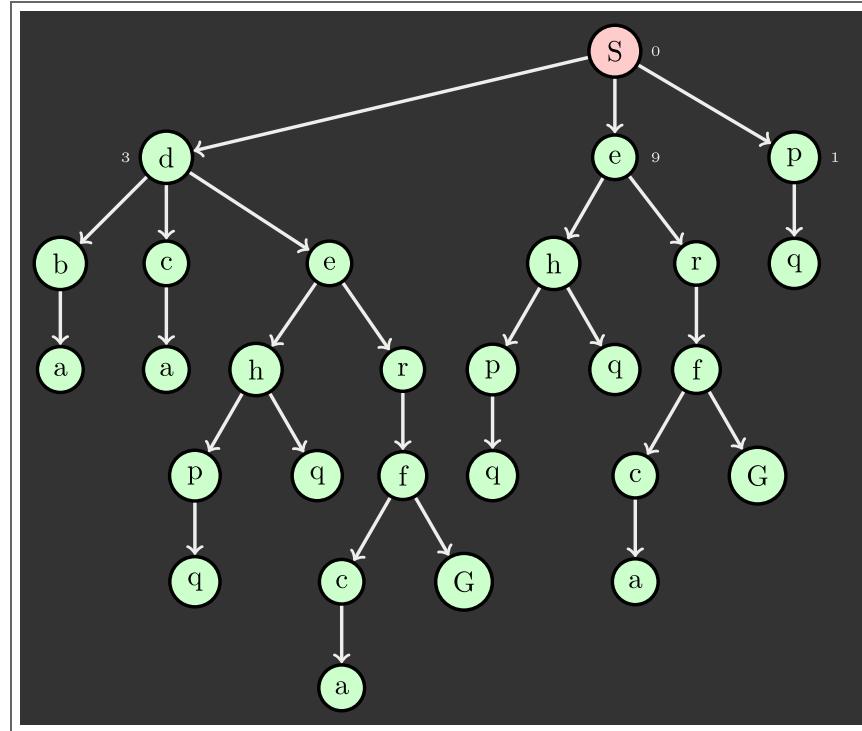
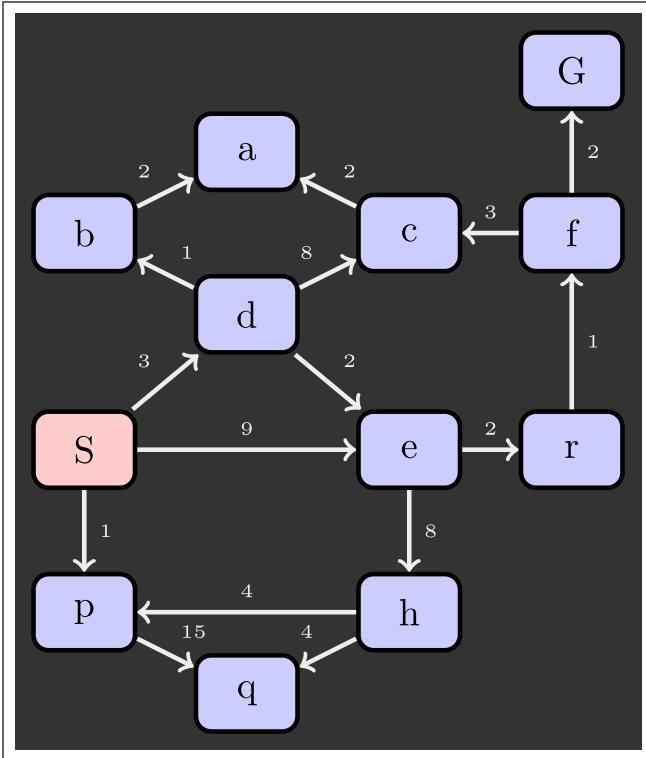
UNIFORM COST SEARCH (UCS)

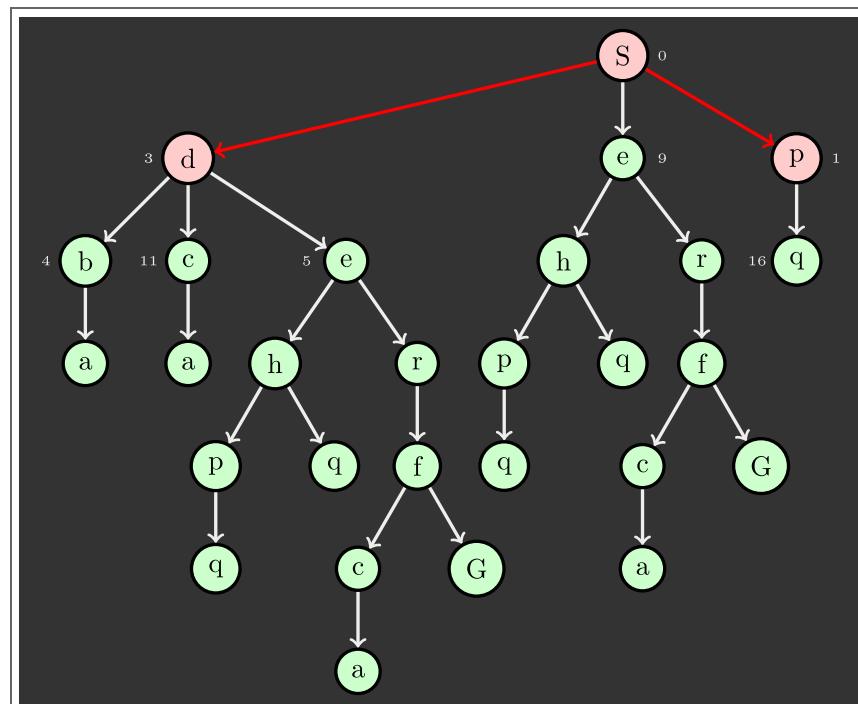
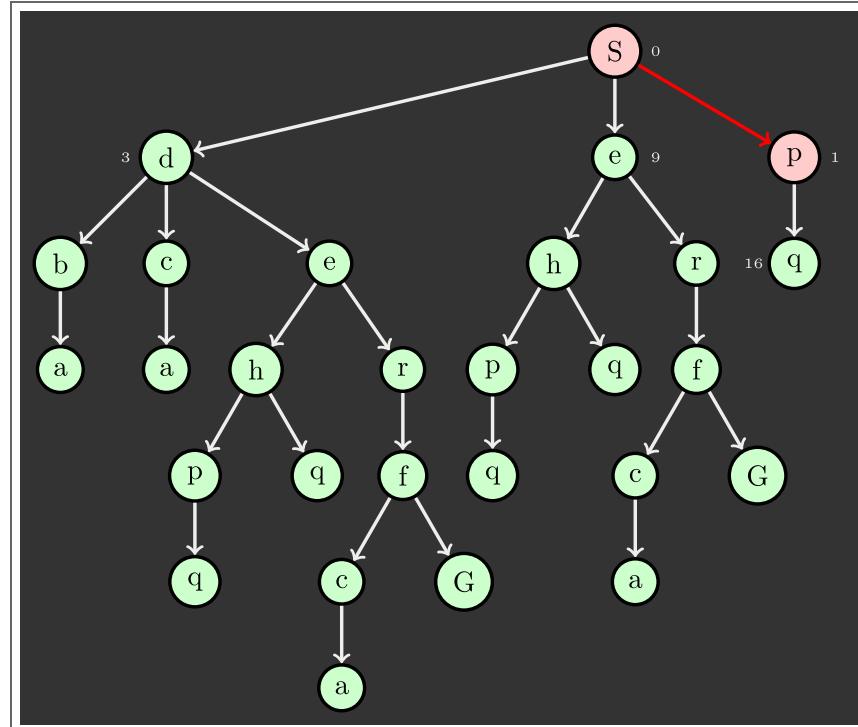
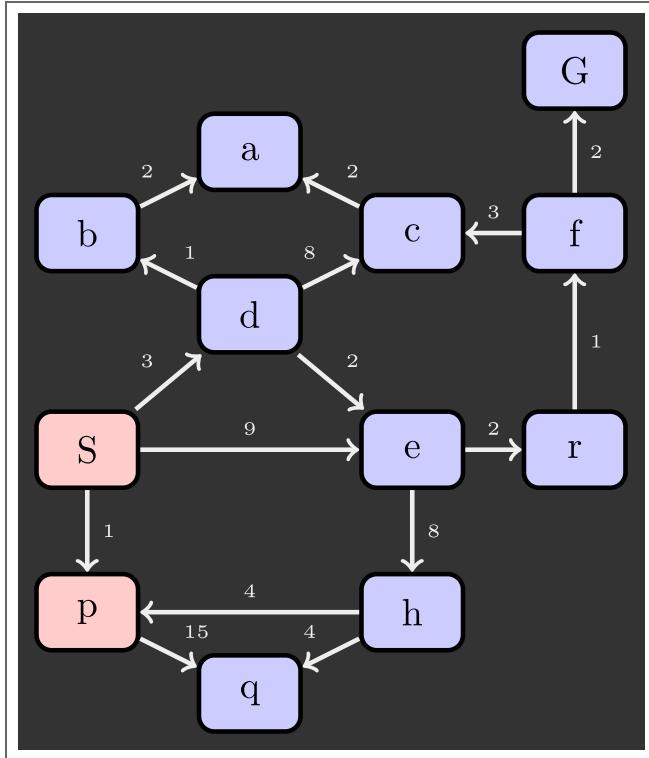
State Space Graph

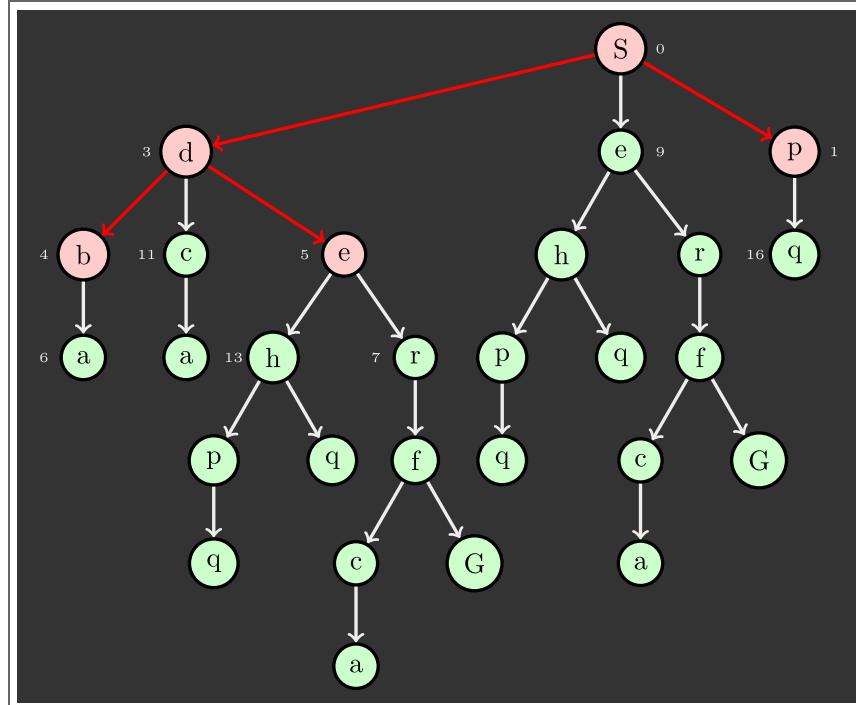
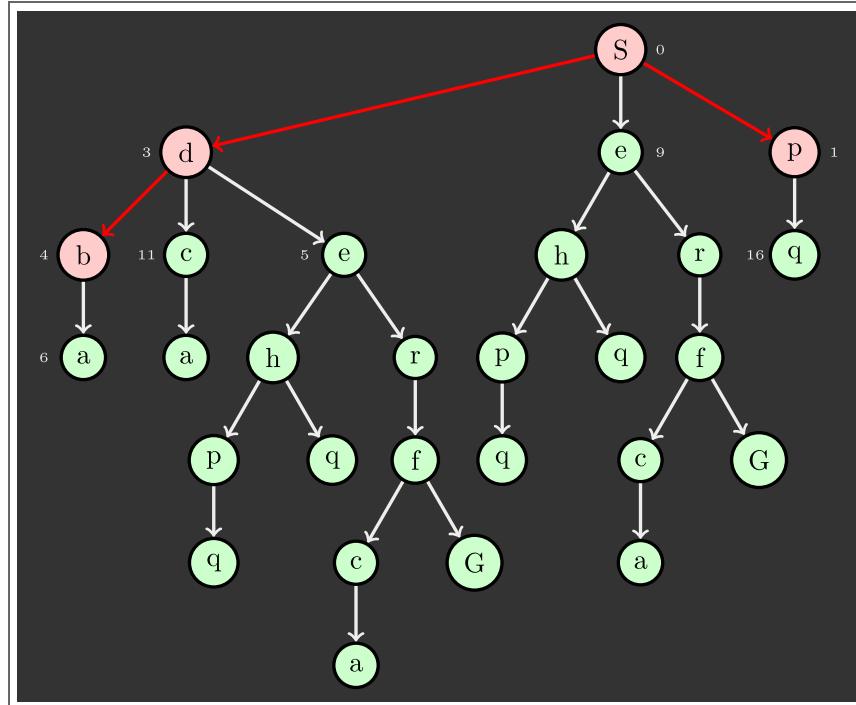
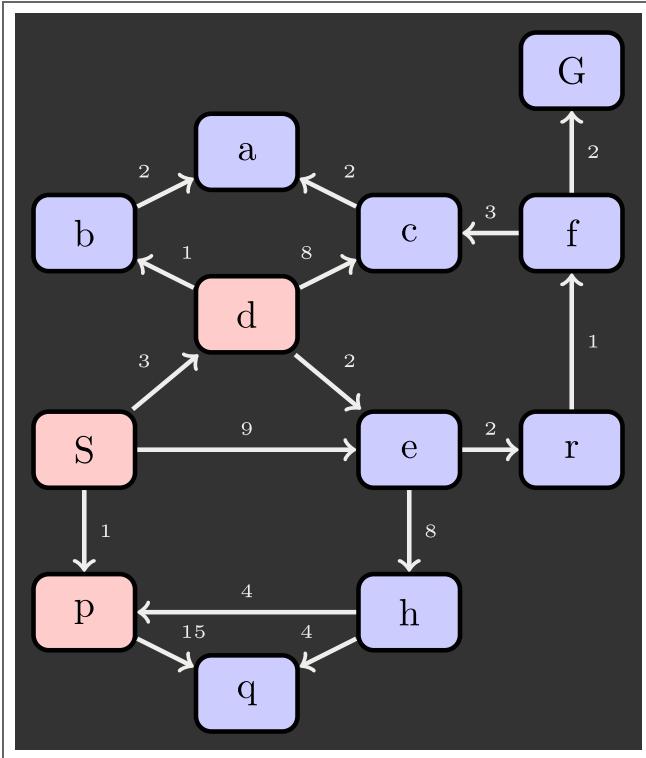


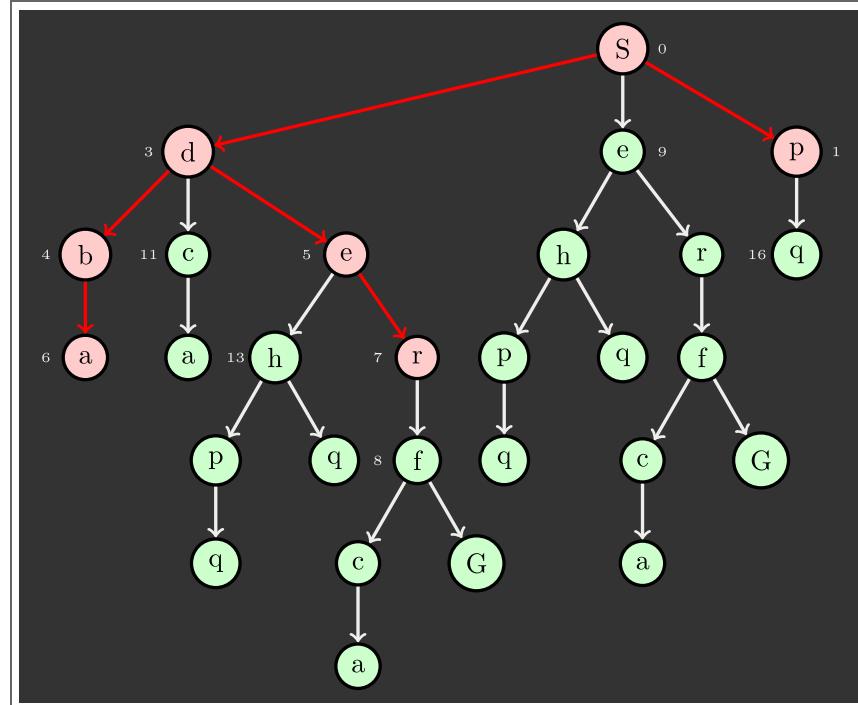
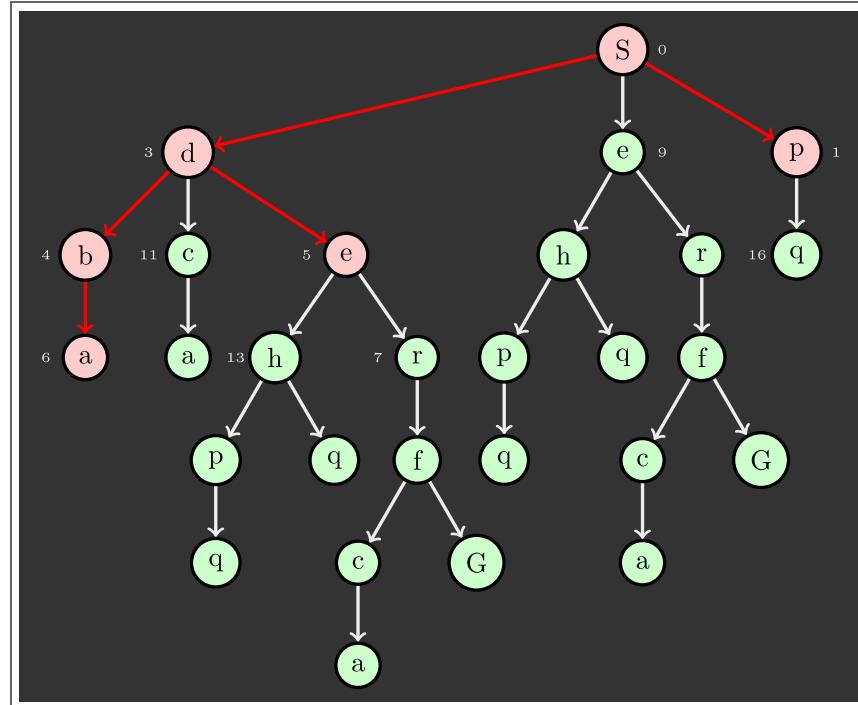
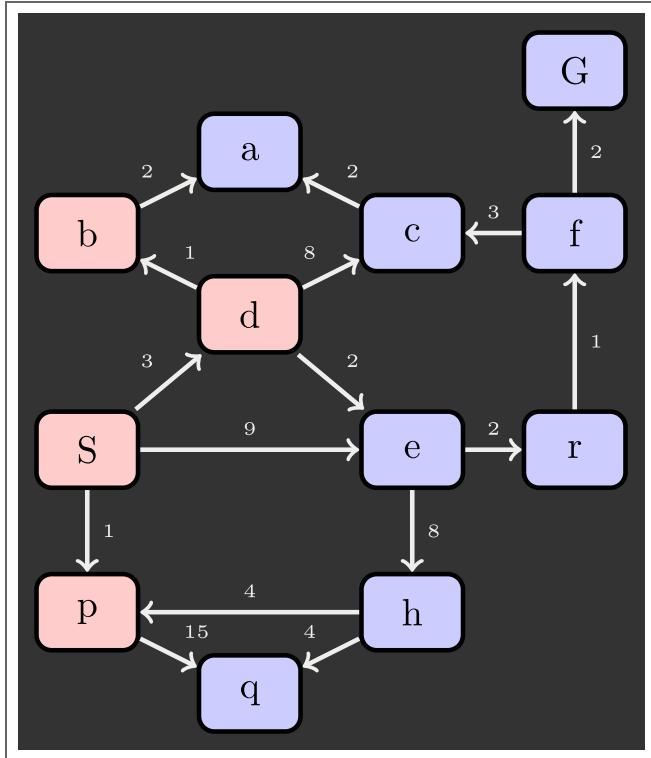
Search Tree

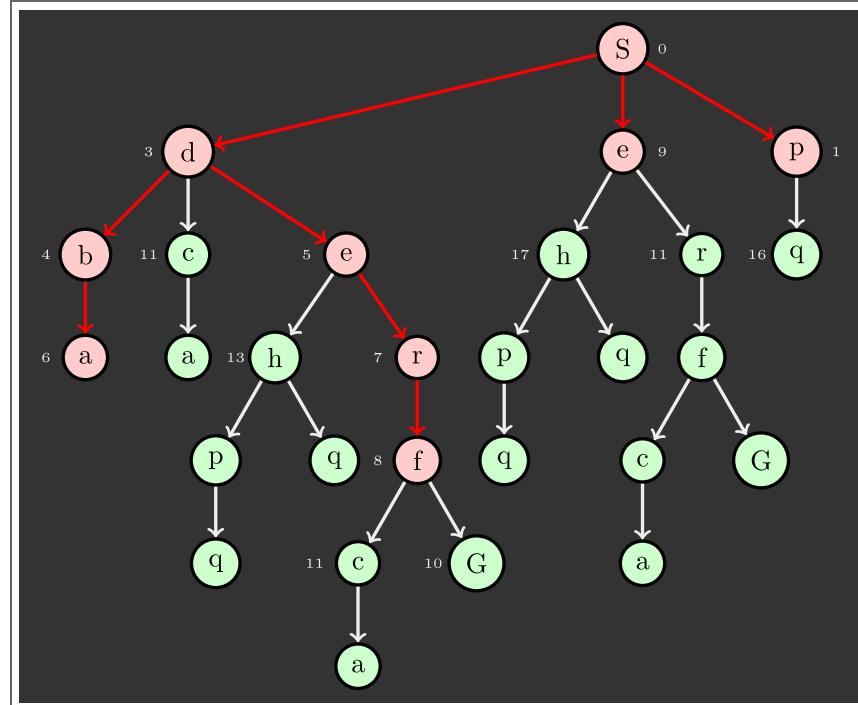
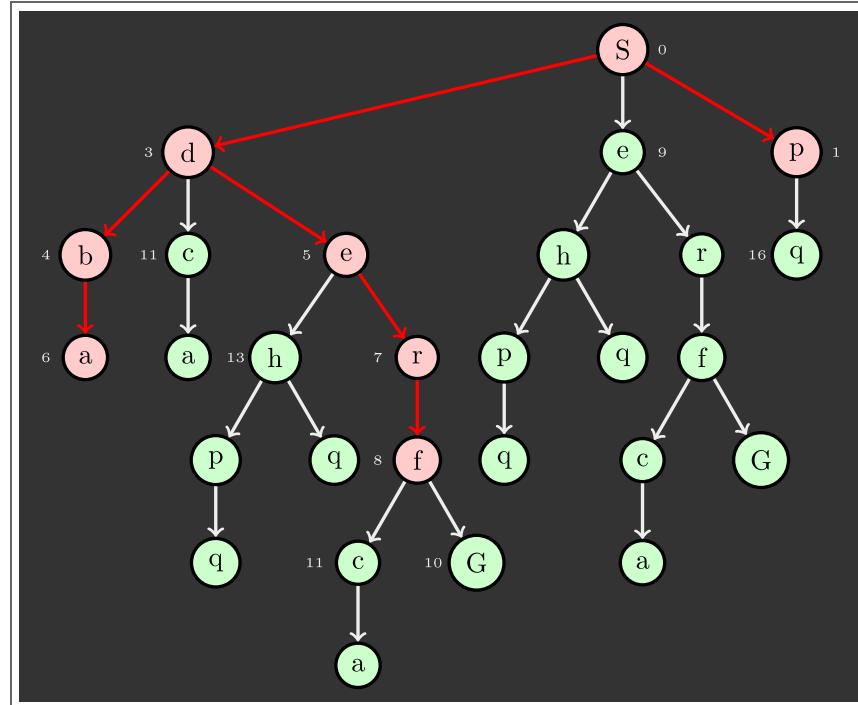
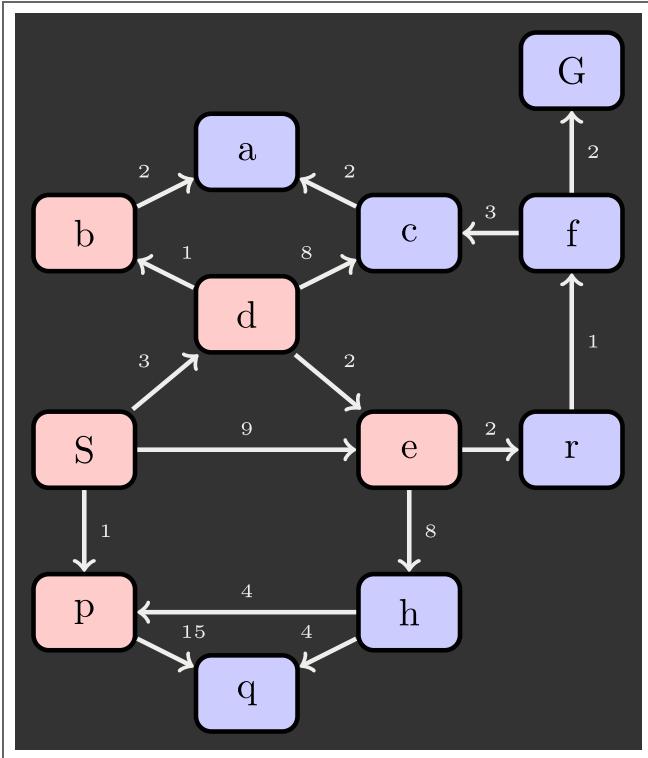


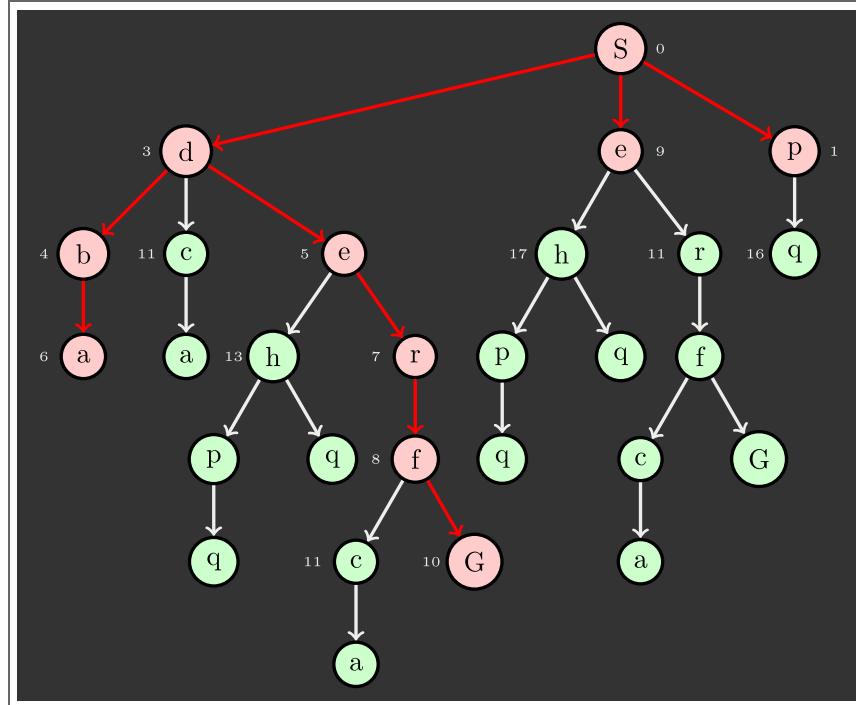
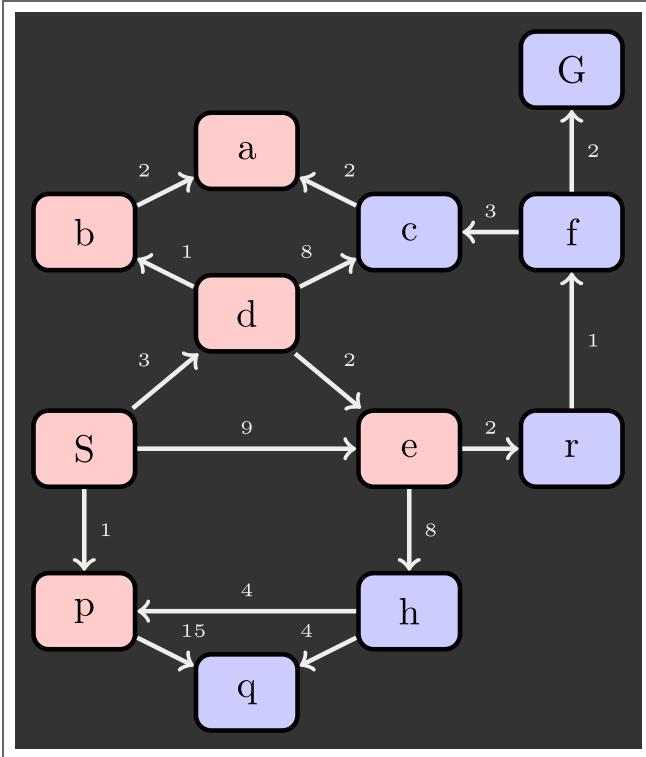








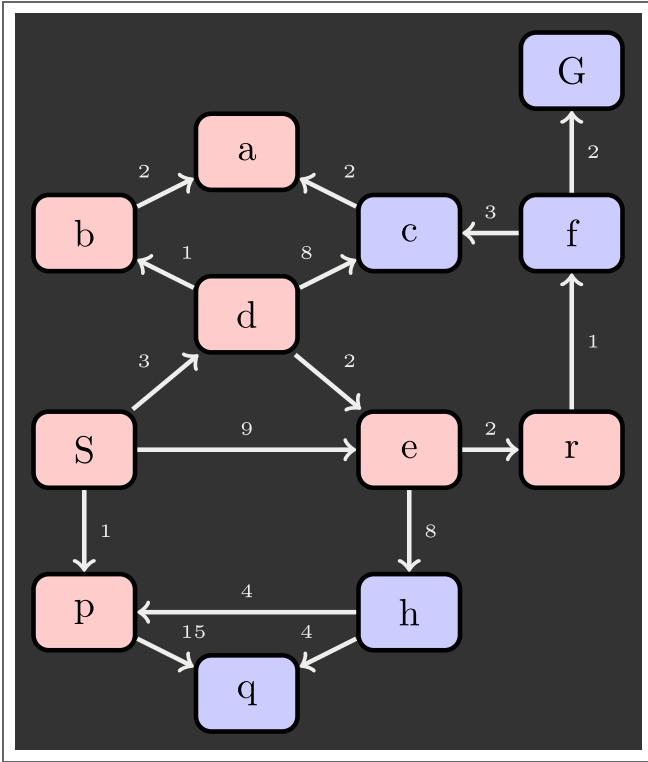




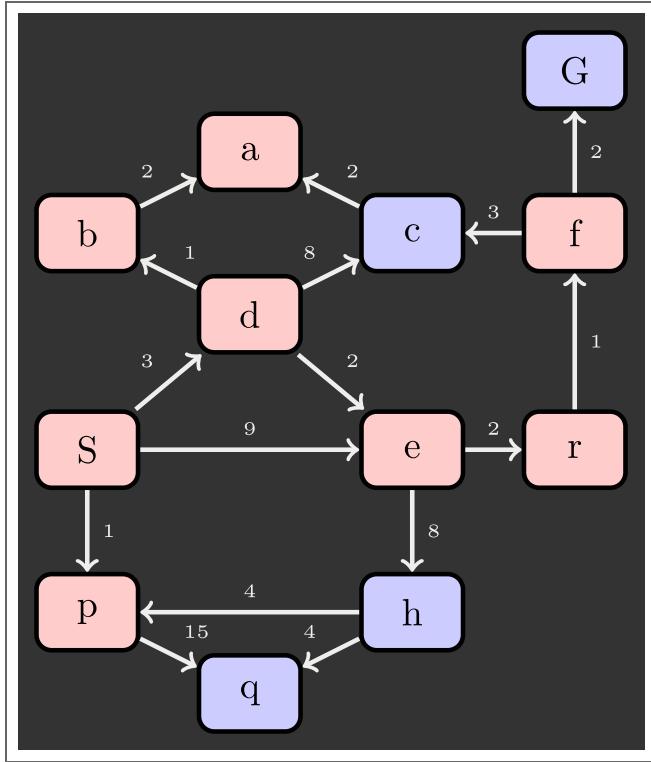
UCS PROPERTIES

What nodes UCS expand?

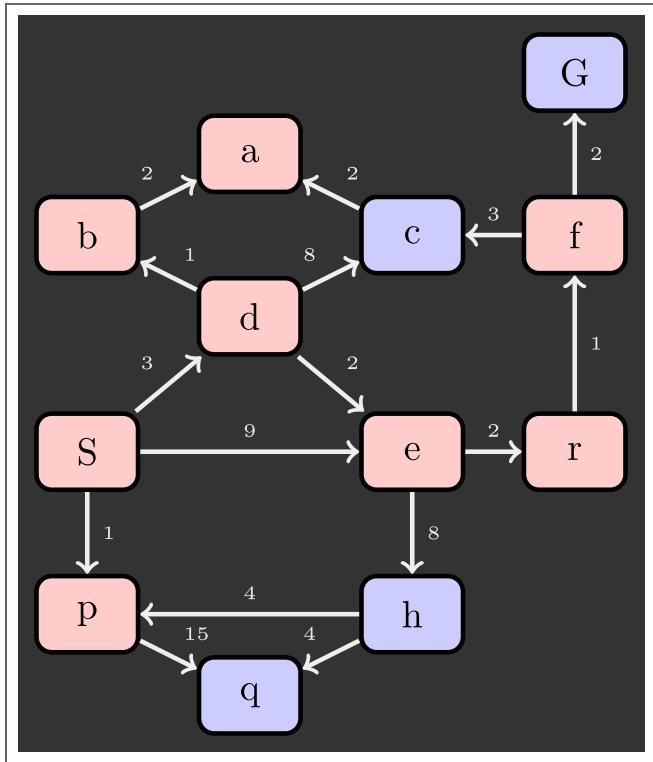
- Processes all nodes with cost less than cheapest solution!
- If that solution costs C^* and arcs cost at least ϵ , then the "effective depth" is roughly $\left(\frac{C^*}{\epsilon}\right)$



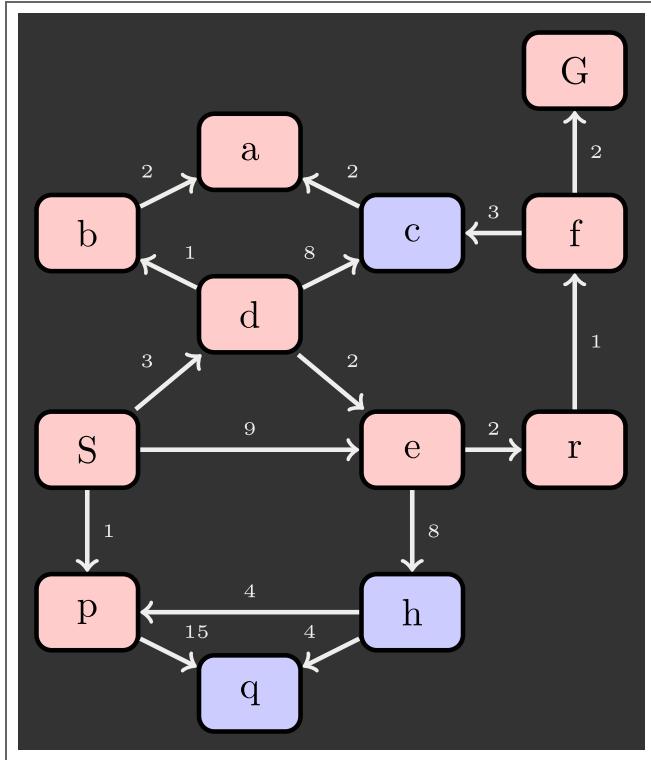
- Takes time $\mathcal{O}\left(b^{\frac{C^*}{\epsilon}}\right)$ (exponential in effective depth)



UNIFORM COST ISSUES



UCS DEMO

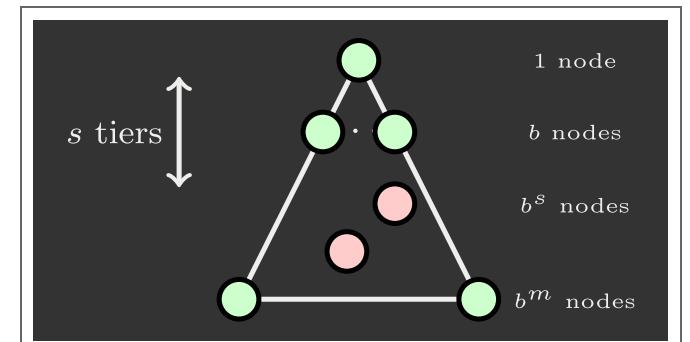


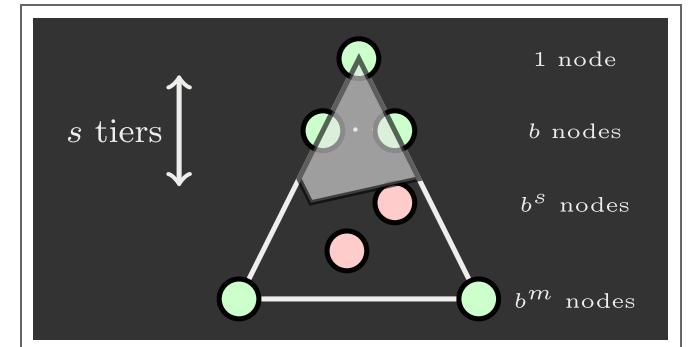
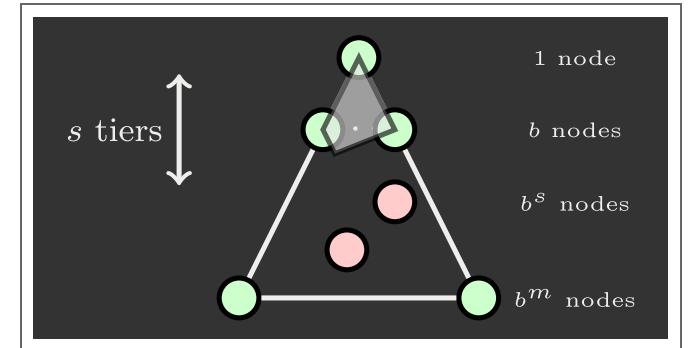
Strategy: expand a cheapest node first

Implementation: fringe is a priority queue (priority: cumulative cost)

How much space does the fringe take?

- Has roughly the last tier, so $\mathcal{O}\left(b^{\frac{c^*}{\epsilon}}\right)$





Is it complete?

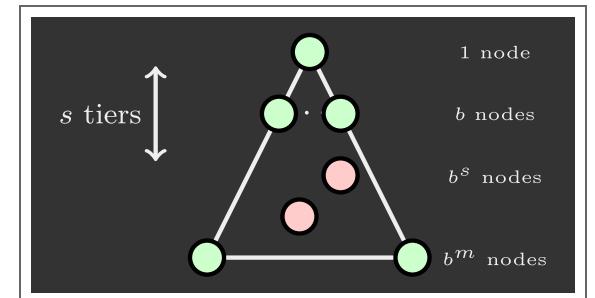
- Assuming best solution has a finite cost and minimum arc cost is positive, yes!

Remember: UCS explores increasing cost contours

The good: UCS is complete and optimal!

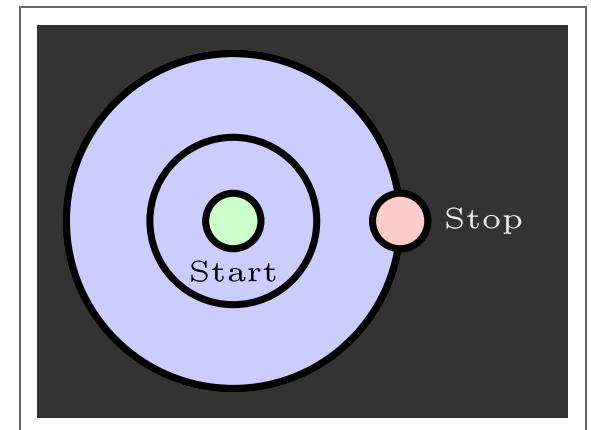
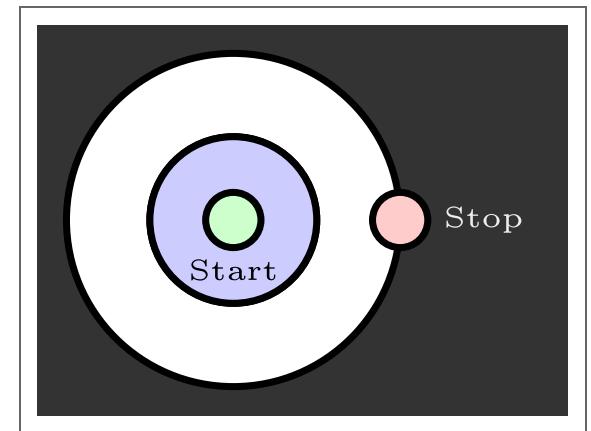
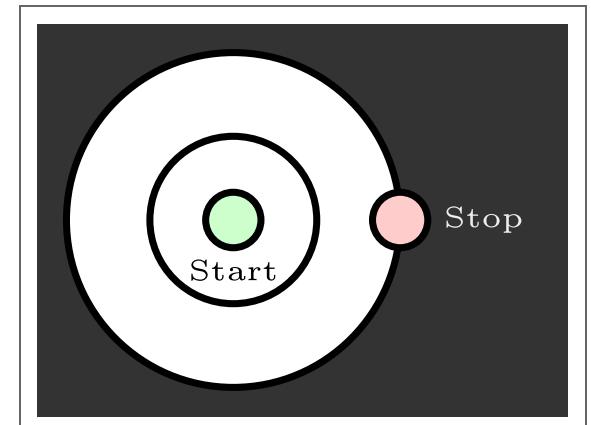
The bad:

- Explores options in every "direction"



- No information about goal location

Will be addressed soon.

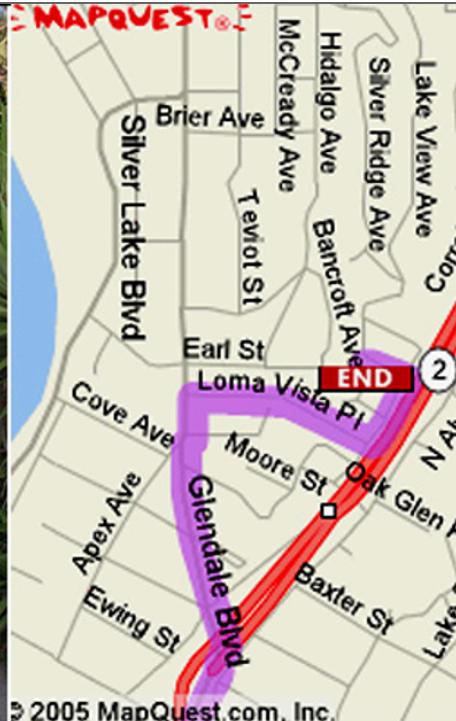


SEARCH AND MODELS

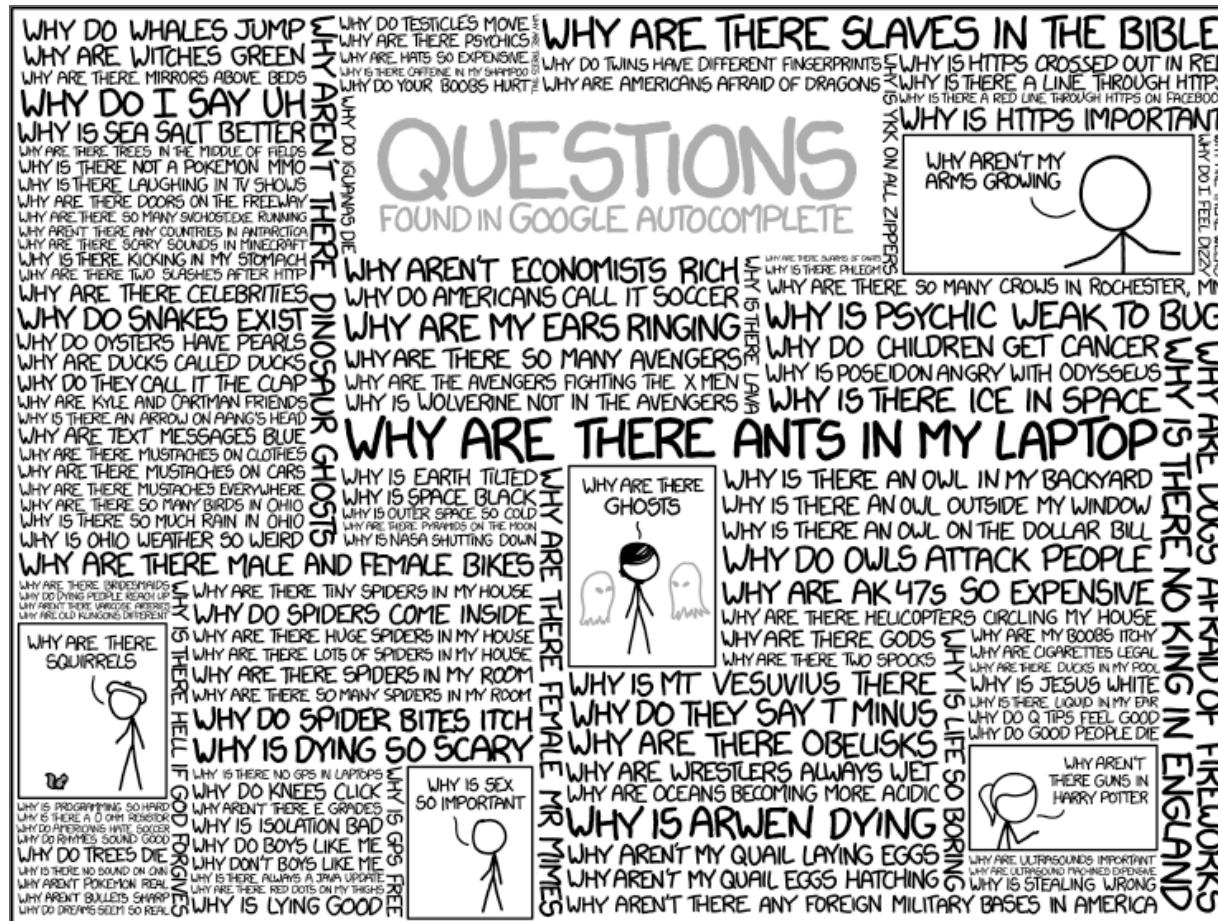
Search operates over models of the world

- › The agent does not actually try all the plans out in the real world.
- › Planning is all “in simulation”
- › Your search is only as good as your models

SEARCH GONE WRONG?



Q & A



XKCD

Speaker notes

