Artificial & Computational Intelligence

AIML CLZG557

M1 : Introduction
&
M2 : Problem Solving Agent using Search

Indumathi V

Guest Faculty,

BITS - WILP

BITS Pilani

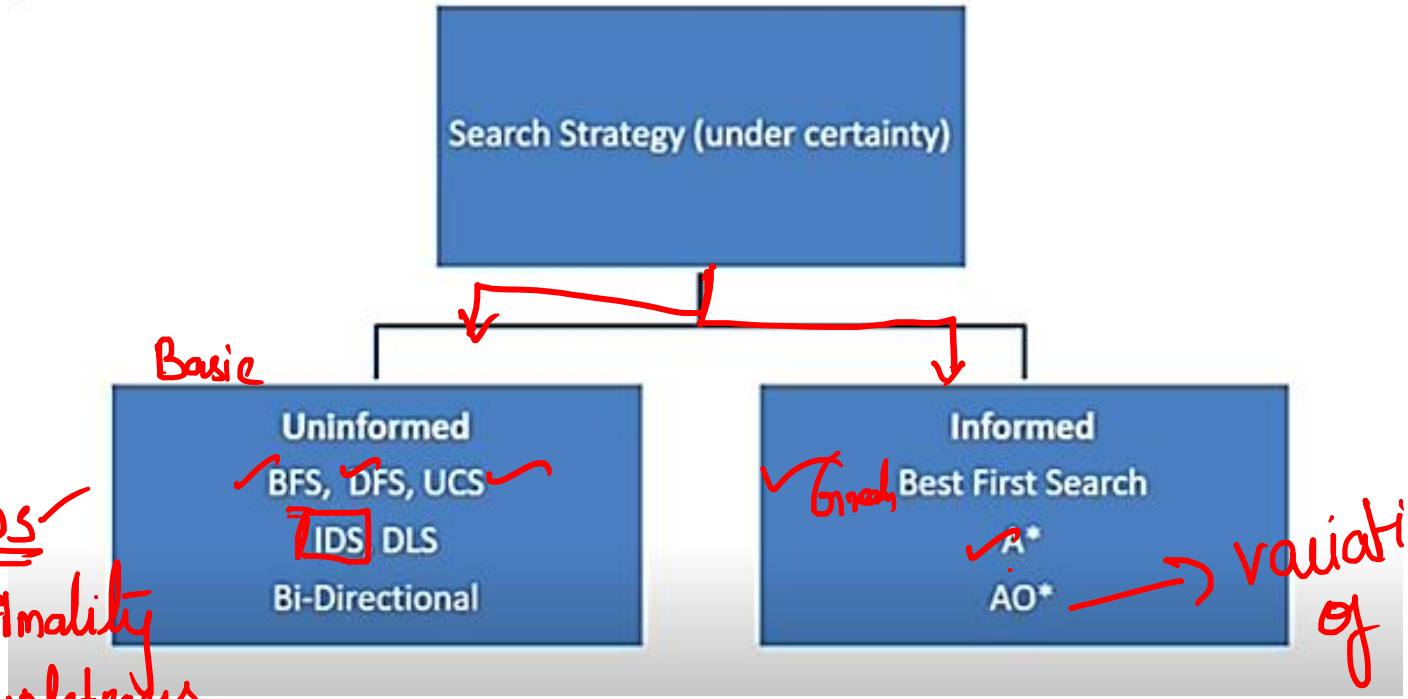
Pilani Campus

Course Plan

M1	Introduction to AI
M2	Problem Solving Agent using Search
M3	Game Playing
M4	Knowledge Representation using Logics
M5	Probabilistic Representation and Reasoning
M6	Reasoning over time, Reinforcement Learning
M7	Ethics in AI

Searching for Solutions

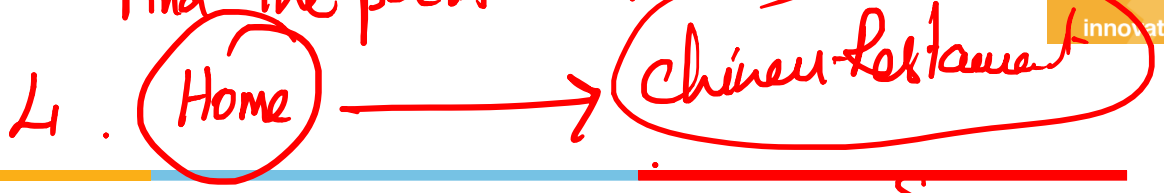
Choosing the current state, testing possible successor function, expanding current state to generate new state is called Traversal. Choice of which state to expand – Search Strategy



Uninformed Search Overview

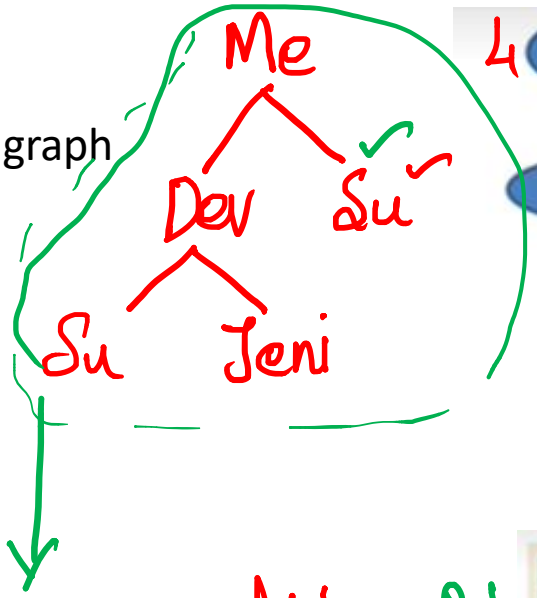
Application

"Find the path"

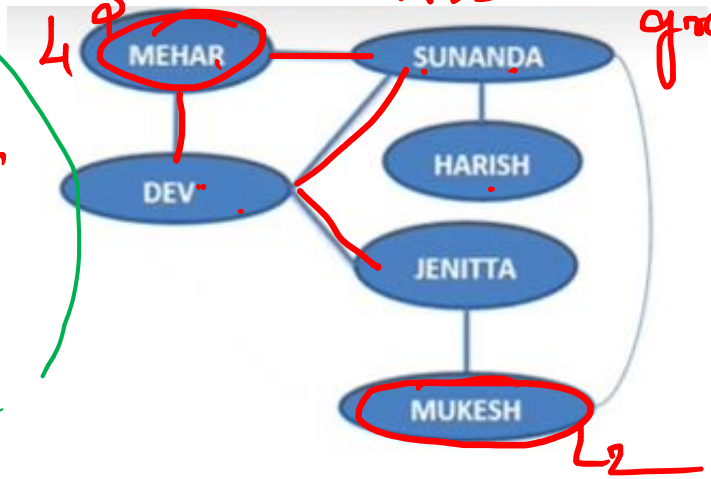


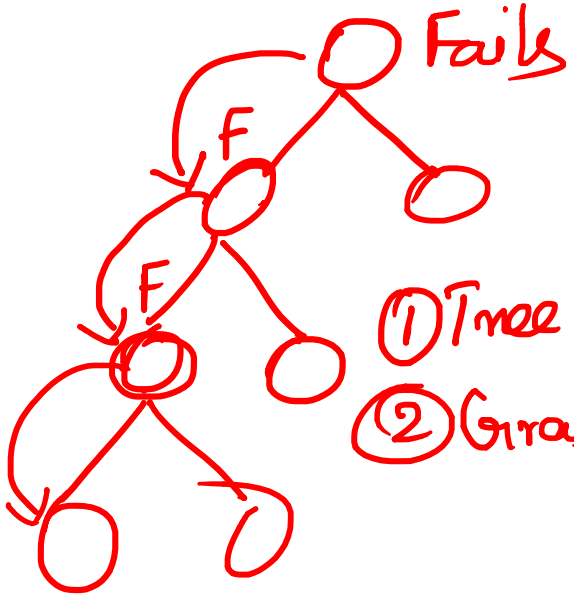
Depth First Search

- Find the Connectedness in a graph
- Topological Sorting



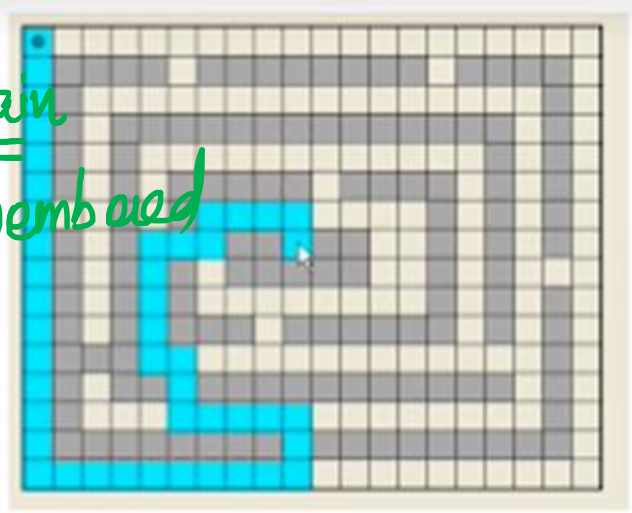
Association graph





① Tree search based Alg → Retain

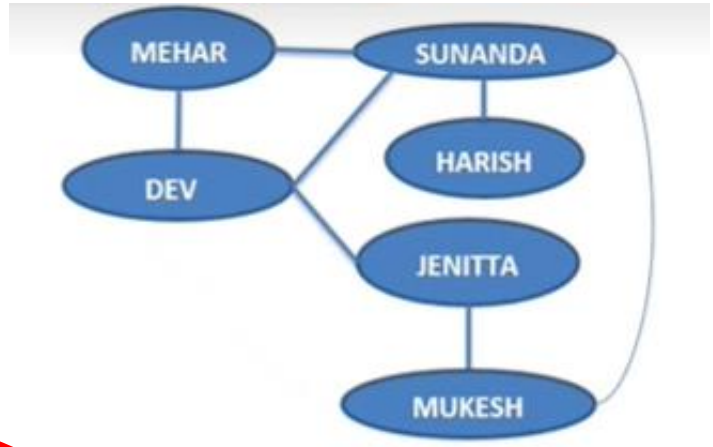
② Graph " — " " → Remembered



Application

Depth First Search

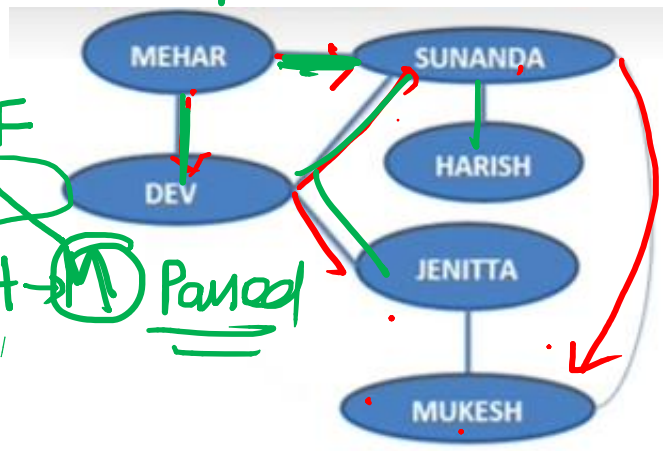
- Find the Connectedness in a graph
- Topological Sorting

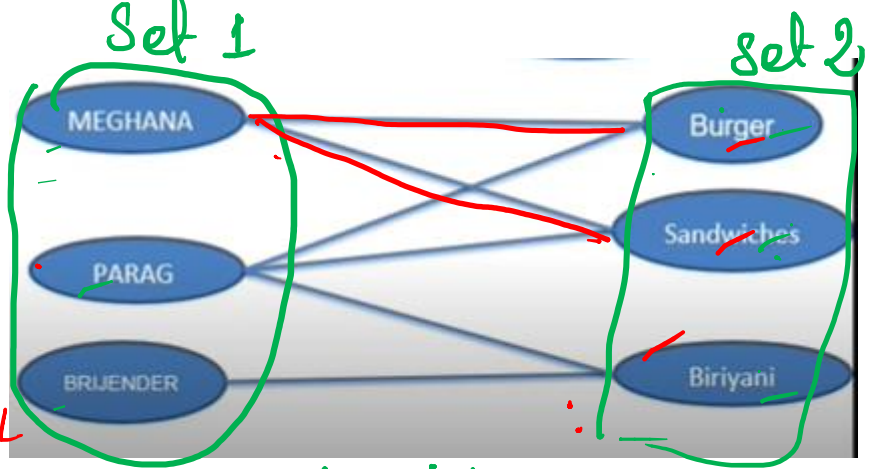


Application

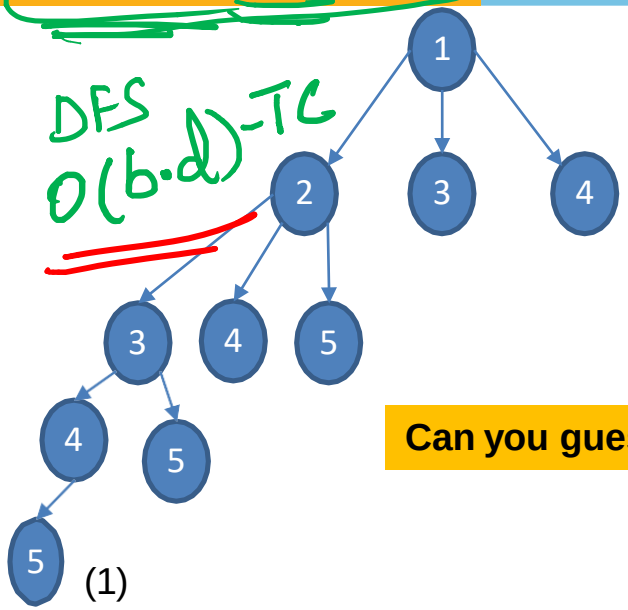
Breadth First Search

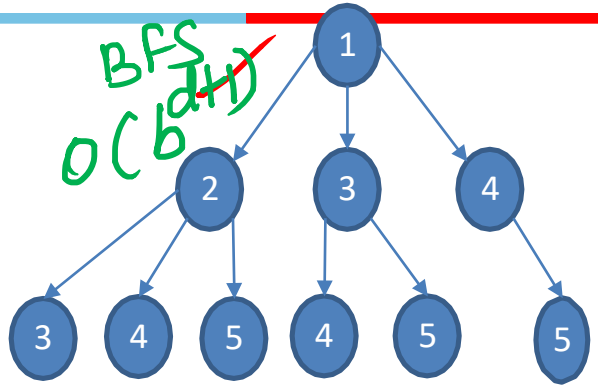
- Finding path in a graph (many solutions)
- Finding the Bipartitions in a graph

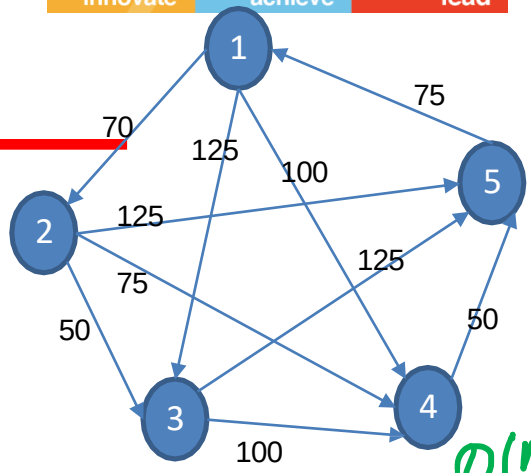




Search Algorithm – Uninformed Example - 2







Can you guess which algorithm are these ?

(1)
(1 2) (1 3) (1 4)
(1 2 3) (1 2 4) (1 2 5) (1 3) (1 4)
(1 2 3 4) (1 2 3 5) (1 2 4) (1 2 5) (1 3) (1 4)
(1 2 3 4 5) (1 2 3 5) (1 2 4) (1 2 5) (1 3) (1 4)

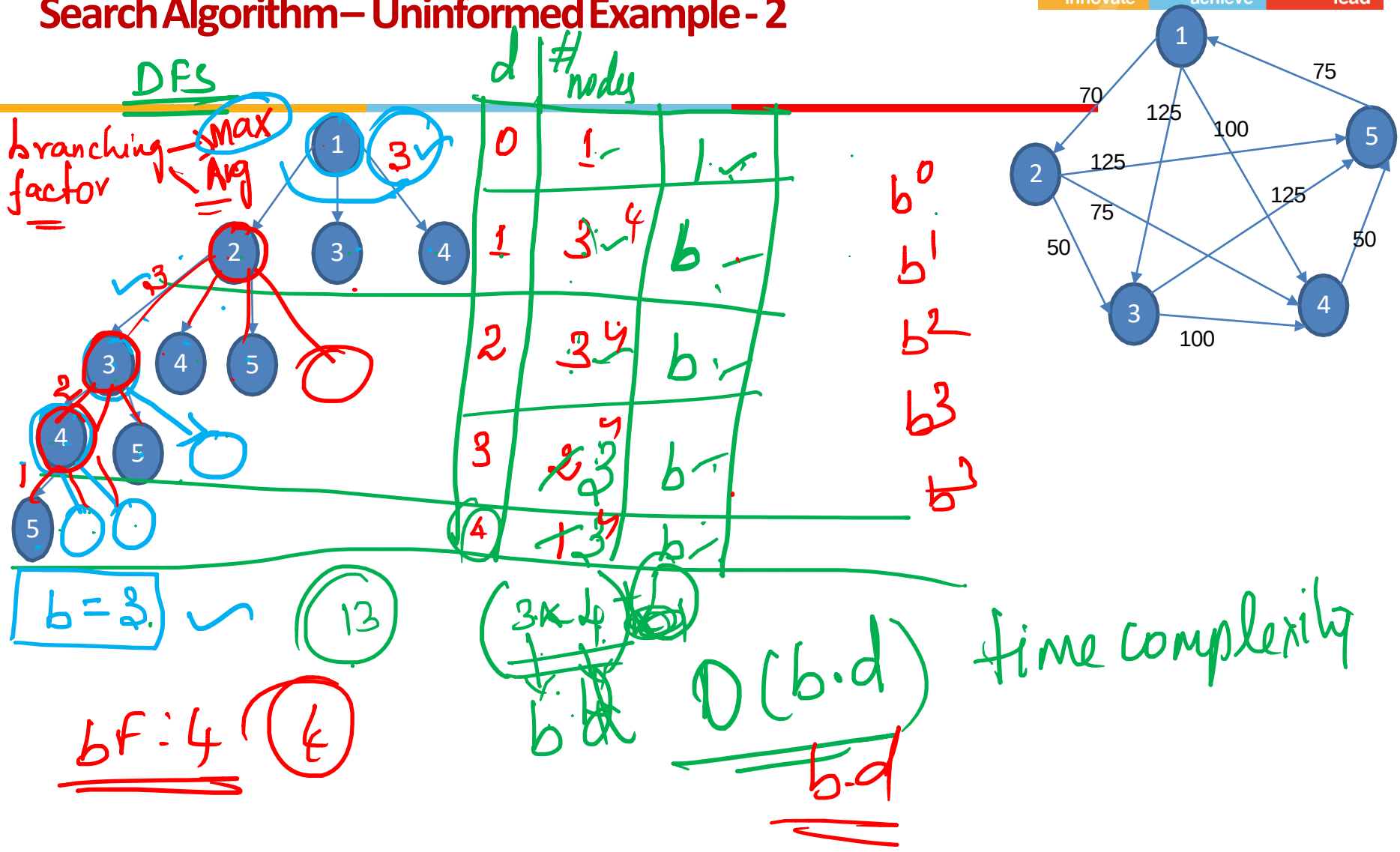
C(1-2-3-4-5) = 70 + 50 + 100 + 50 =270
Expanded : 4
Generated : 10
Max Queue Length : 6

(1)
(1 2) (1 3) (1 4)
TEST FAILED

(1 3) (1 4) (1 2 3) (1 2 4) (1 2 5)
(1 2 3) (1 2 4) (1 2 5) (1 3 4) (1 3 5) (1 4 5)
TEST PASSED

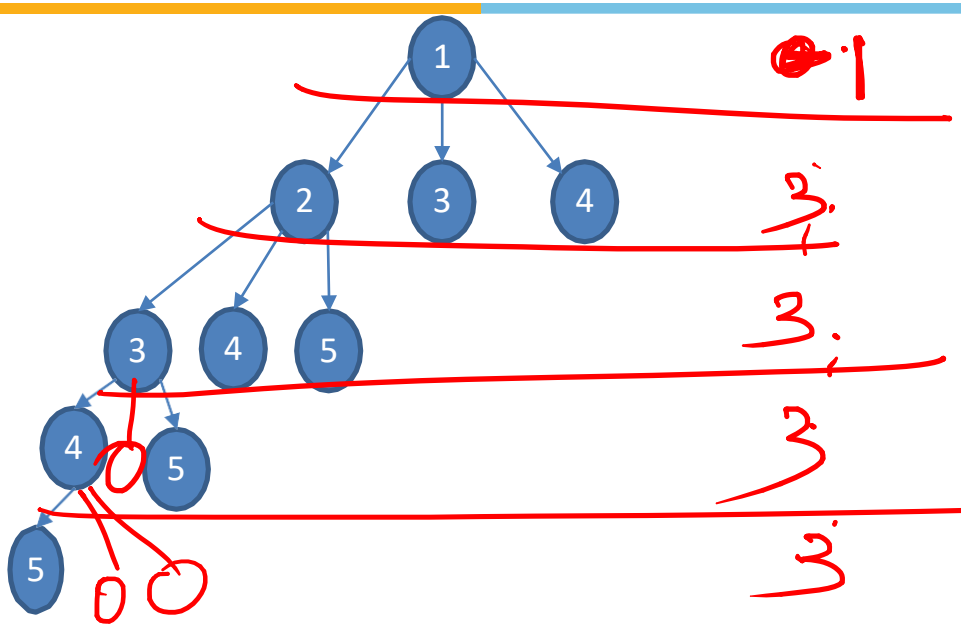
C(1-2-5) = 70 + 125 =195
Expanded : 4
Generated : 10
Max Queue Length : 6

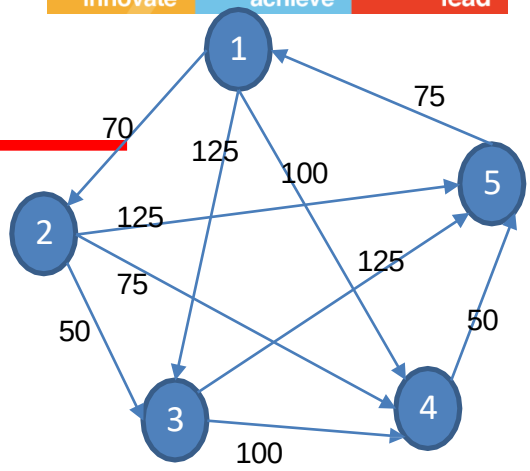
Search Algorithm – Uninformed Example - 2



Search Algorithm – Uninformed Example - 2

Space DFS





m → depth @ which DFS is going

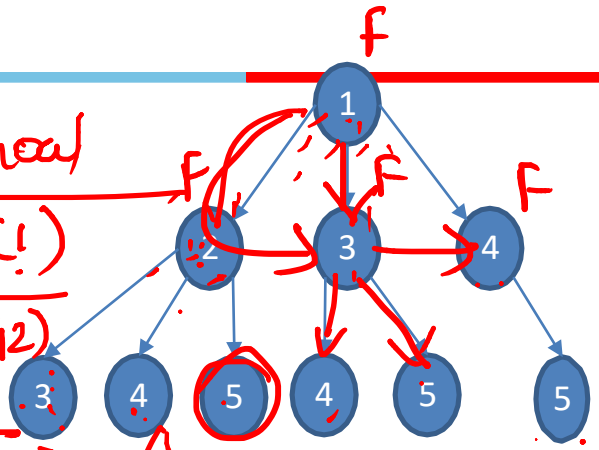
d → depth @ which goal is founded.

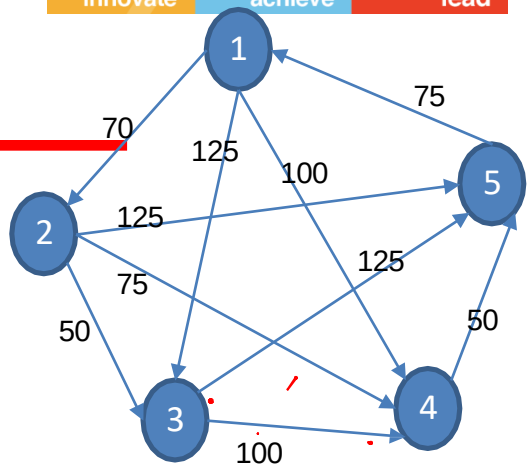
$O(b * m + 1)$

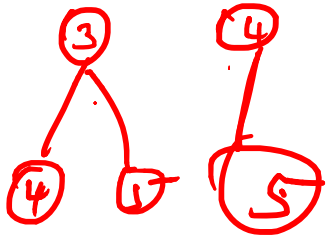
Search Algorithm – Uninformed Example - 2

BFS @ end of queue.

open list	closed list	Goal
(1) (1)	–	F(1)
(12) (13) (14) (3)	(1)	F(12)
(13) (14) (123) (124) (125) (5)	(1) (12)	F(13)
(14) (123) (124) (125) (134) (135) (6)	(1) (12) (13)	F(14)
(123) (124) (125) (134) (135) (145) (6)	(1) (12) (13) (14)	F(123)
(124) (125) (134) (135) (145) (7) (1234) (1235)	(1) (12) (13) (14) (123)	F(124)
(125) (134) (135) (145) (1234) (1235) (1245) (9)	(1) (12) (13) (14) (123) + (124) (11)	P(125)



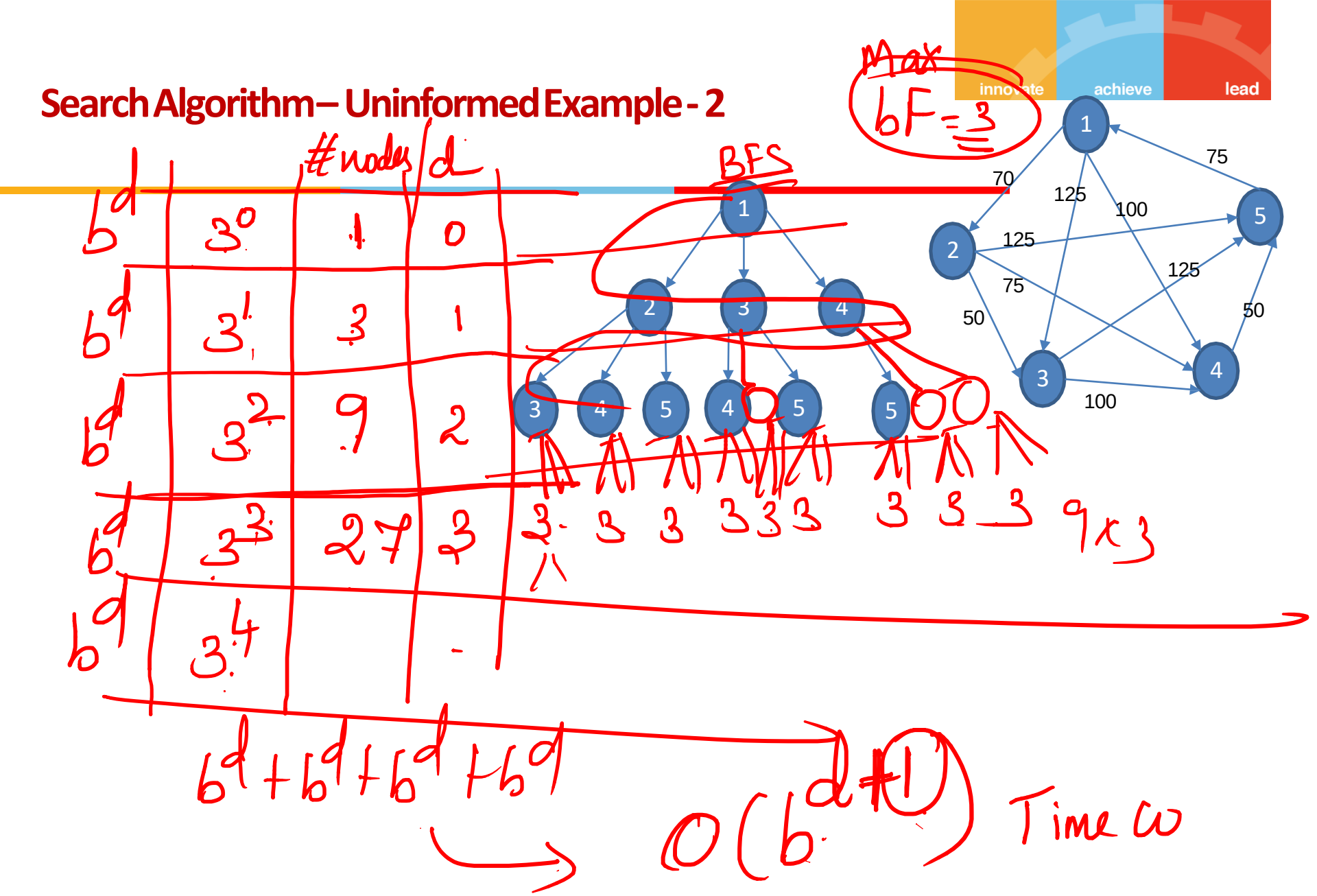




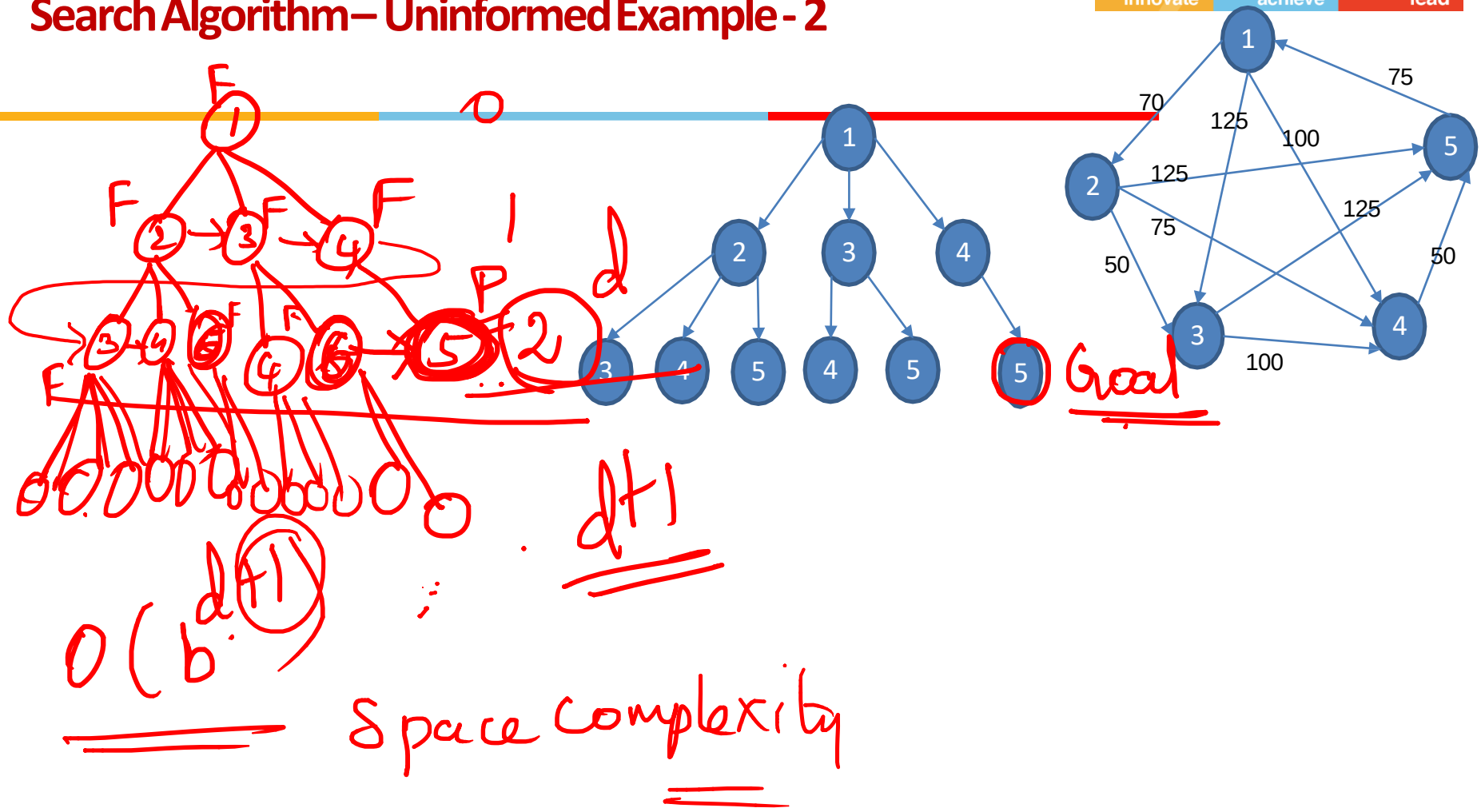
3 4 5 4 5 5

Max queue length : 7

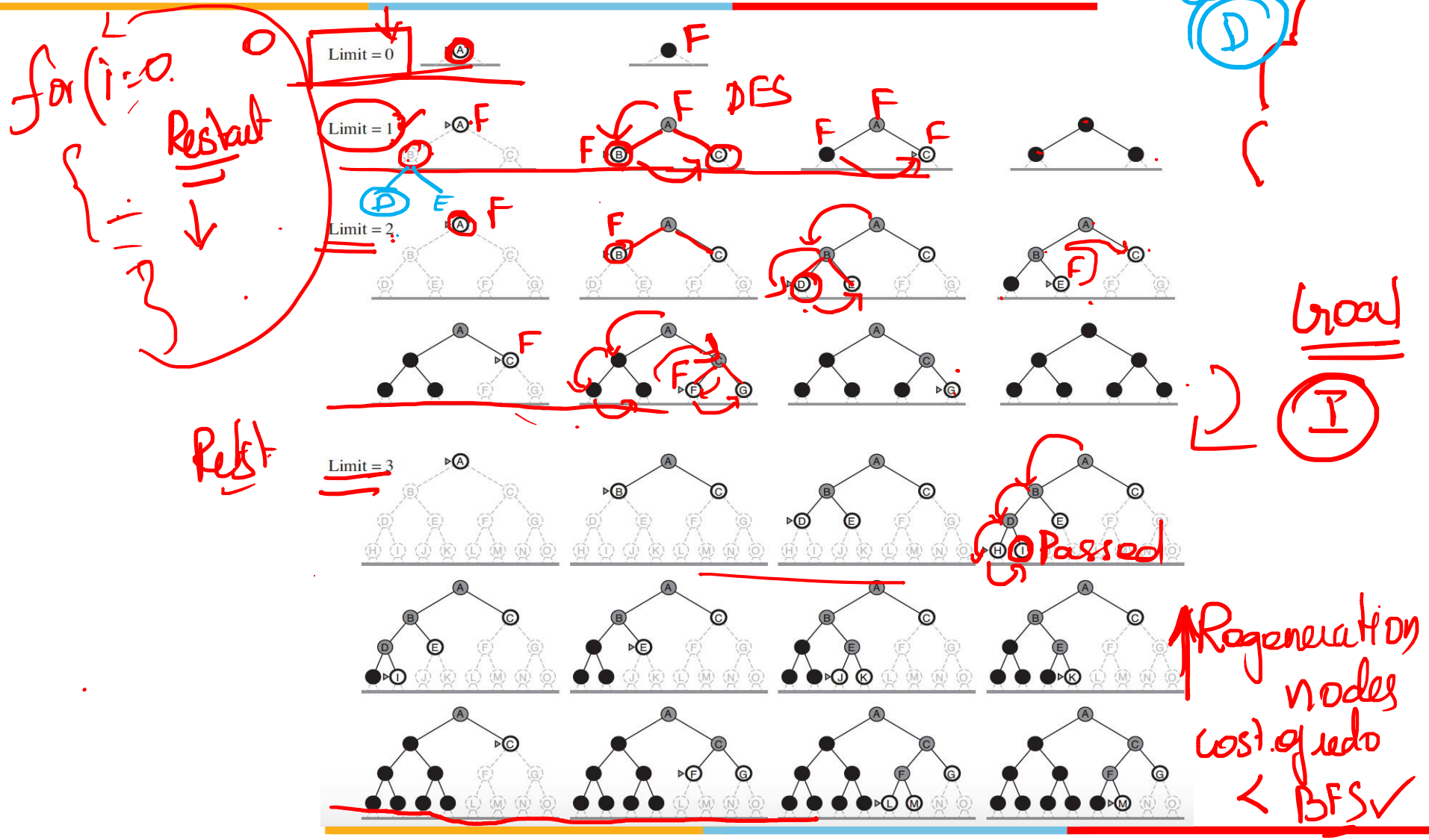
Search Algorithm– Uninformed Example - 2



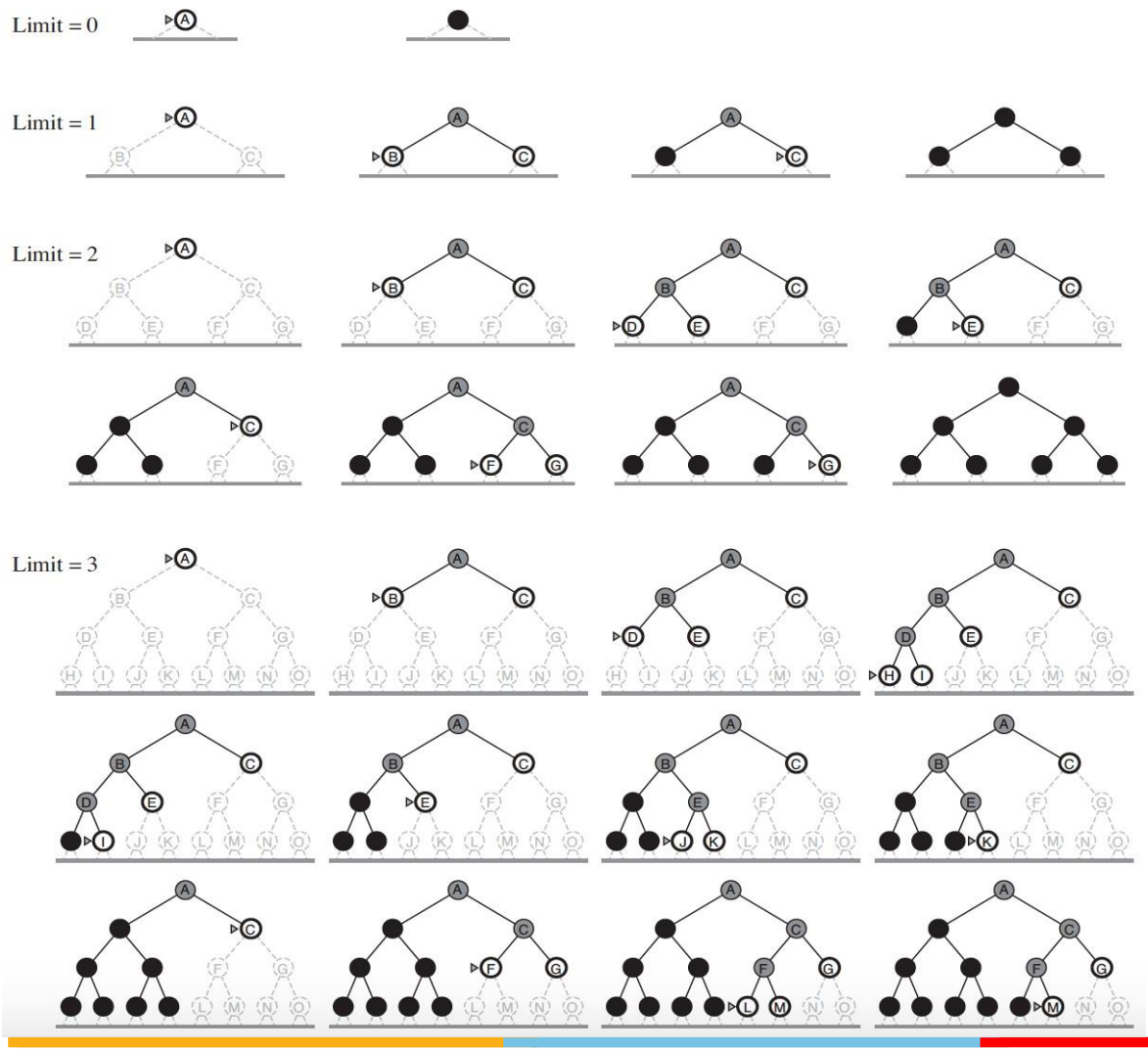
Search Algorithm– Uninformed Example - 2



Iterative Deepening Depth First Search (IDS)



Iterative Deepening Depth First Search (IDS)

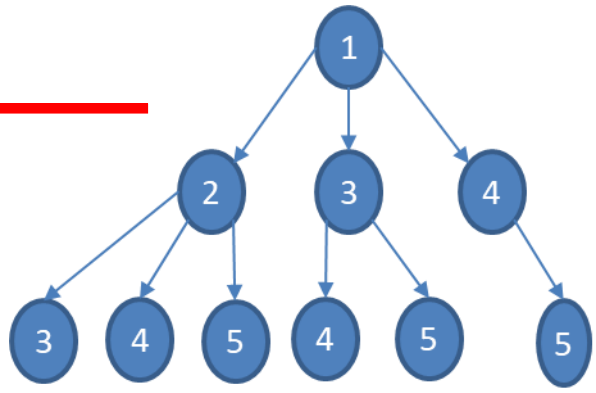


Algorithm Tracing

Students must follow this in the exams for all the search algorithms in addition to the search tree constructions. The ordering of the Open Lists must be in consistent with the algorithm with a note on the justification of the order expected!

Iter	Open List / Frontiers / Fringes	Closed List	Goal Test
1.	(1)		Fail on (1)
2.			

Sample Evaluation of the Algorithm -BFS



Complete – If the shallowest goal node is at a depth d, BFS will eventually find it by generating all shallower nodes

Optimal – Not necessarily. Optimal if path cost is non-decreasing function of depth of node. E.g., all actions have same cost

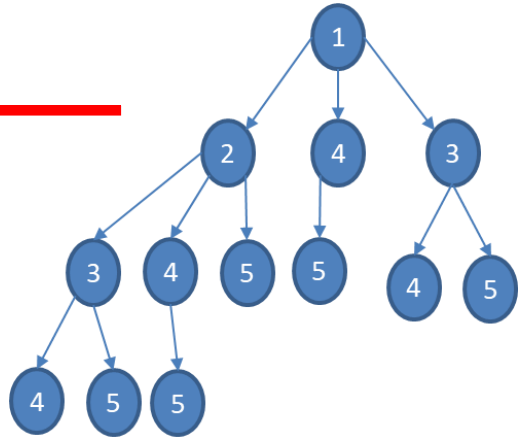
Time Complexity – $G(b^d)$ b - branching factor, d – depth

- Nodes expanded at depth 1 = b
- Nodes expanded at depth 2 = b^2
- Nodes expanded at depth d = b^d
- Goal test is applied during generation, time complexity would be $G(b^{d+1})$

Space Complexity – $G(b^d)$

- $G(b^{d-1})$ in explored set
- $G(b^d)$ in frontier set

Uniform Cost Search – Evaluation



Completeness – It is complete if the cost of every step > small +ve constant ∈

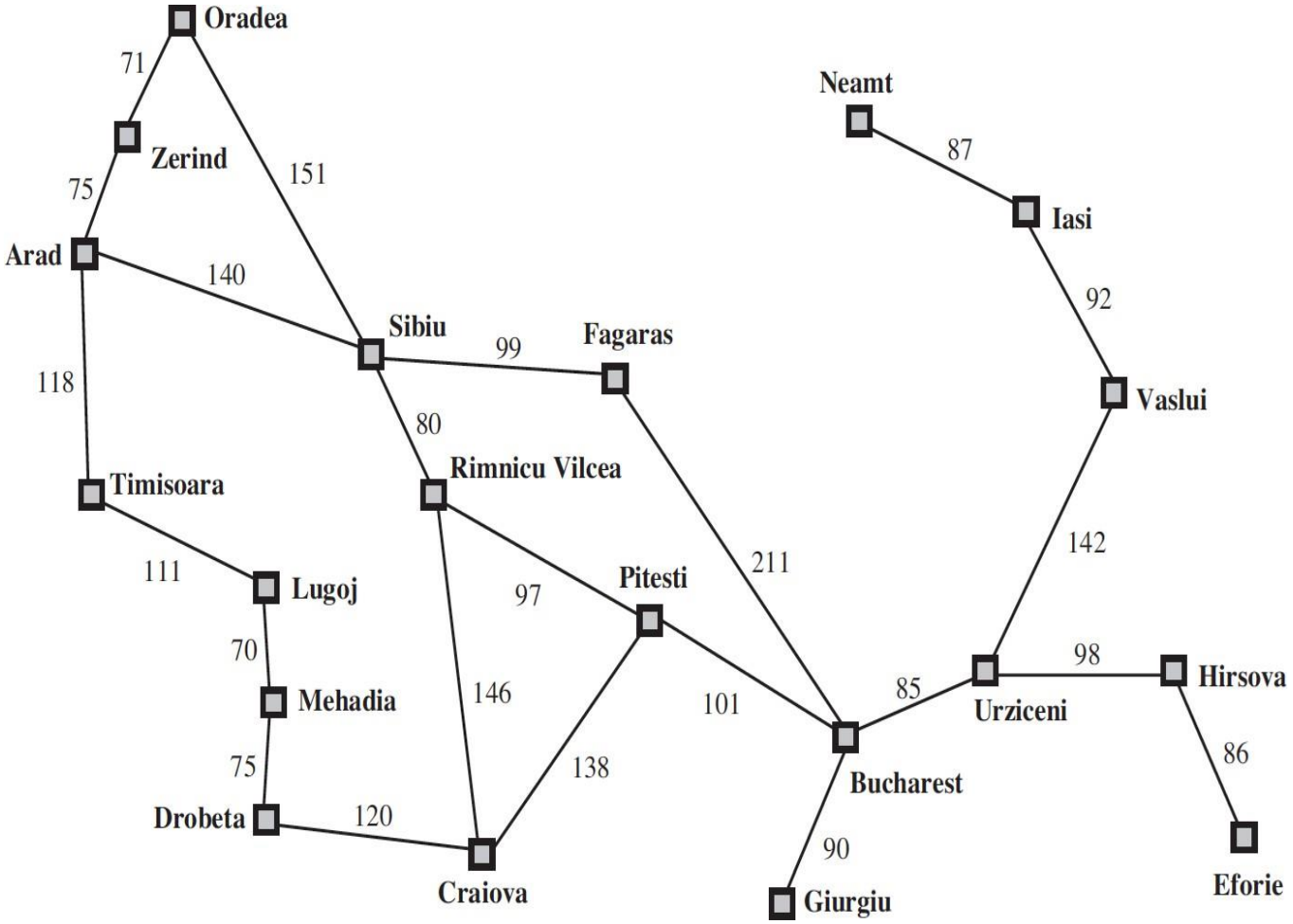
- It will stuck in infinite loop if there is a path with infinite sequence of zero cost actions

Optimal – It is Optimal. Whenever it selects a node, it is an optimal path to that node.

Time and Space complexity – Uniform cost search is guided by path costs not depth or branching factor.

- If C* is the cost of optimal solution and ∈ is the min. action cost
- Worst case complexity = $G(b^{1+\frac{C^*}{\epsilon}})$,
- When all action costs are equal → $G(b^{d+1})$, the BFS would perform better
  - As Goal test is applied during expansion, Uniform Cost search would do extra work

Tree Search Vs Graph Search


Oradea
71
Neamt
87
Zerind
151
75
Iasi
Arad
140
92
Sibiu
99
Fagaras
118
Vaslui
80
Rimnicu Vilcea
Timisoara
142
111
211
Lugoj
97
Pitesti
70
98
Hirsova
Mehadia
146
101
85
Urziceni
75
86
138
Bucharest
Drobeta
120
90
Craiova
Giurgiu
Eforie

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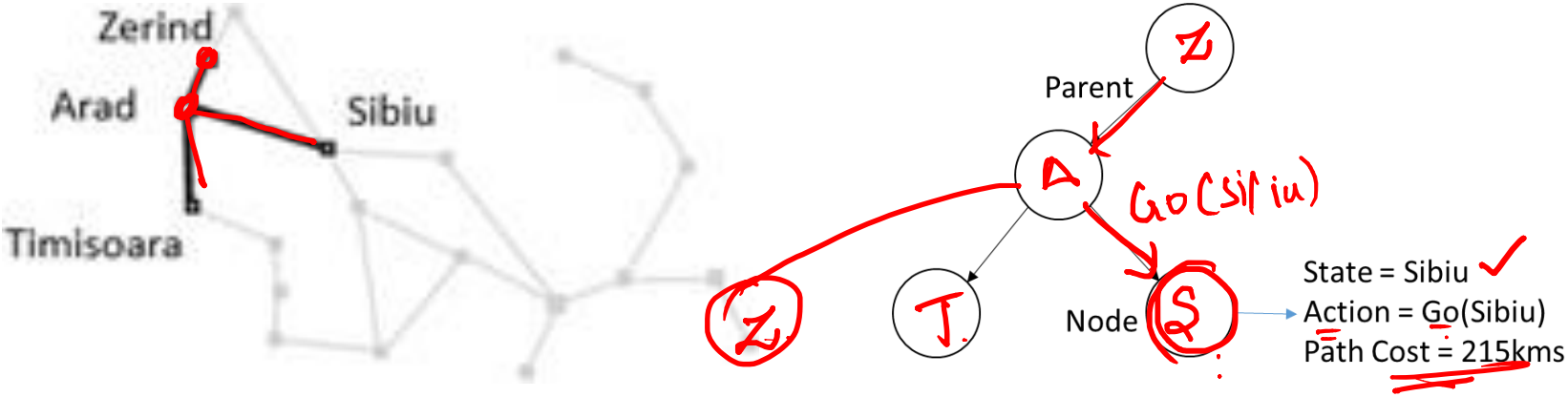
Coding Aspects

For each node n of the tree,

- **n.STATE** : the state in the state space to which node corresponds
- **n.PARENT** : the node in the search tree that generated this node
- **n.ACTION** : the action that was applied to parent to generate the node
- **n.PATH-COST** : the cost, denoted by g(n), of the path from initial state to node



Algorithm Tracing

Students must follow this in the exams for all the search algorithms in addition to the search tree constructions. The ordering of the Open Lists must be in consistent with the algorithm with a note on the justification of the order expected!

Iter	Open List / Frontiers / Fringes	Goal Test
1.	(1)	Fail on (1)
2.	(1 3), (1 4), (1 2)	Fail on (1 3)

NO Closed list

Tree Search Algorithms

```
function Tree-Search (problem, strategy) returns a solution, or failure
        initialize the search tree using the initial state of problems
        loop do
                if there are no candidate for expansion
                        then return failure
                choose: leaf node for expansion according to strategy
                if the node contains a goal state
                        then return the corresponding solution
                else
                        Expand the node
                        Add the resulting nodes to the search tree
        end
```

Tree Search Vs Graph Search Algorithms

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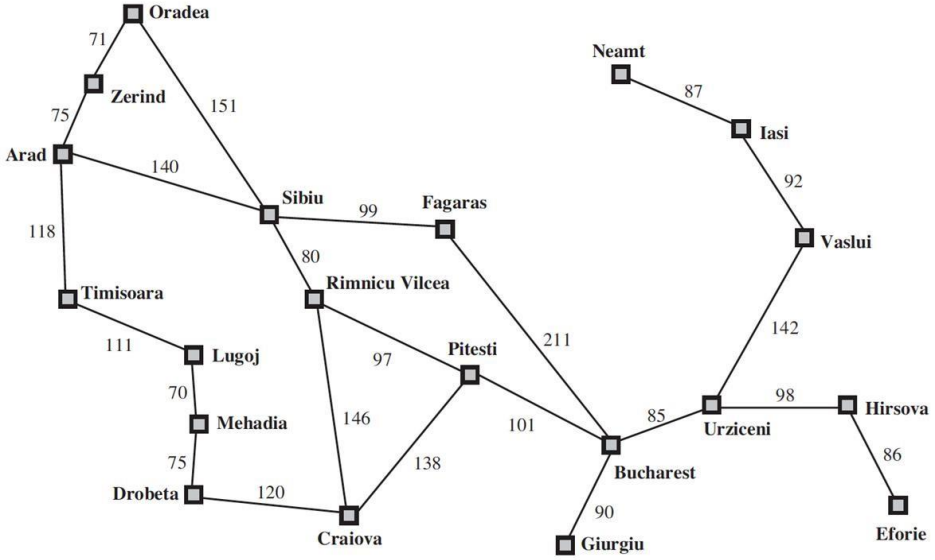
Coding Aspects

Need:

Redundant Path Problem : More than one way to reach a state from another.

Infinite Loop Path Problem



Start : Arad

Goal : Craiova

Tree Search Vs Graph Search Algorithms

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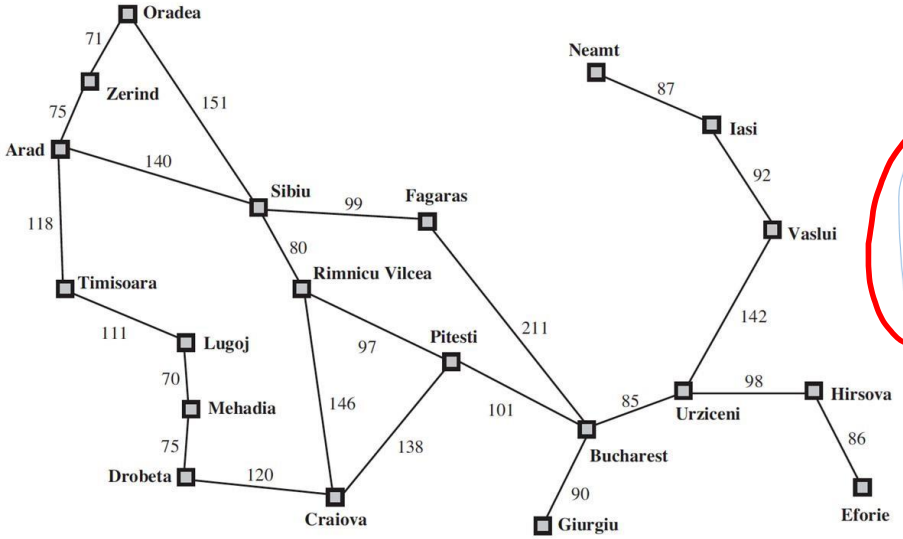
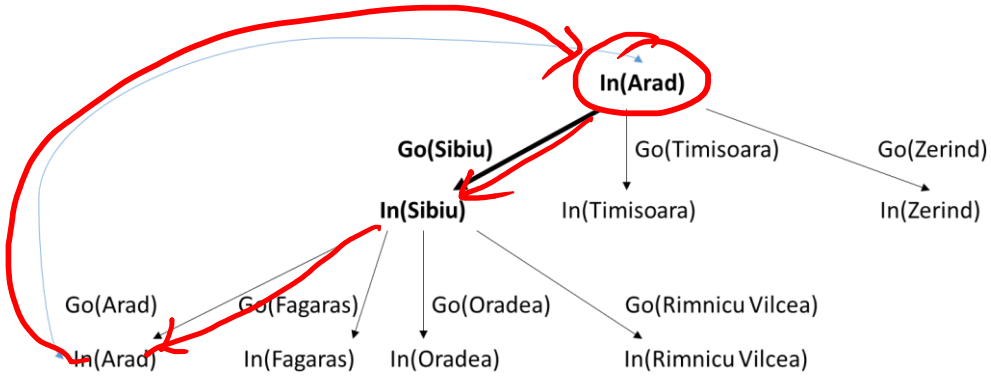
Coding Aspects

Need:

Redundant Path Problem

Infinite Loop Path Problem: Repeated State generated by looped path existence.





Start : Arad

Goal : Craiova

Algorithm Tracing

Students must follow this in the exams for all the search algorithms in addition to the search tree constructions. The ordering of the Open Lists must be in consistent with the algorithm with a note on the justification of the order expected!

Iter	Open List / Frontiers / Fringes	**Closed List**	Goal Test
1.	(1)		Fail on (1)
2.	(1 3), (1 4), (1 2)	(1)	Fail on (1 3)

Search

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Coding Aspects

For each node n of the tree,

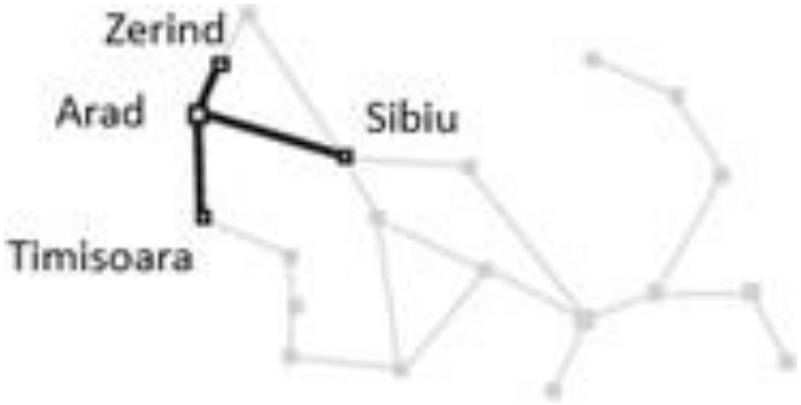
n.STATE : the state in the state space to which node corresponds

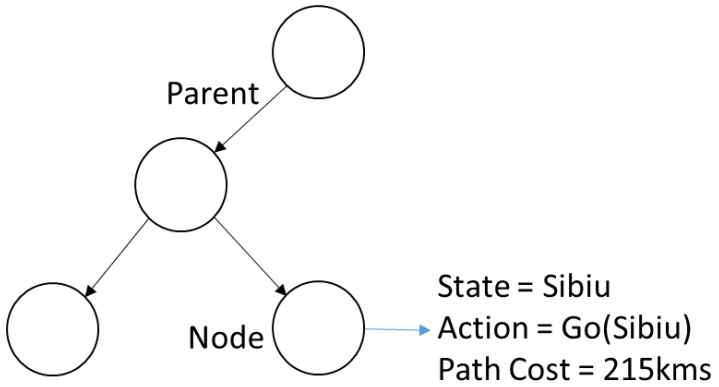
n.PARENT : the node in the search tree that generated this node

n.ACTION : the action that was applied to parent to generate the node

n.PATH-COST : the cost, denoted by g(n), of the path from initial state to node

n.VISITED : the boolean indicating if the node is already visited and tested (**or)** a global SET of visited nodes





Tree Search Vs Graph Search Algorithms

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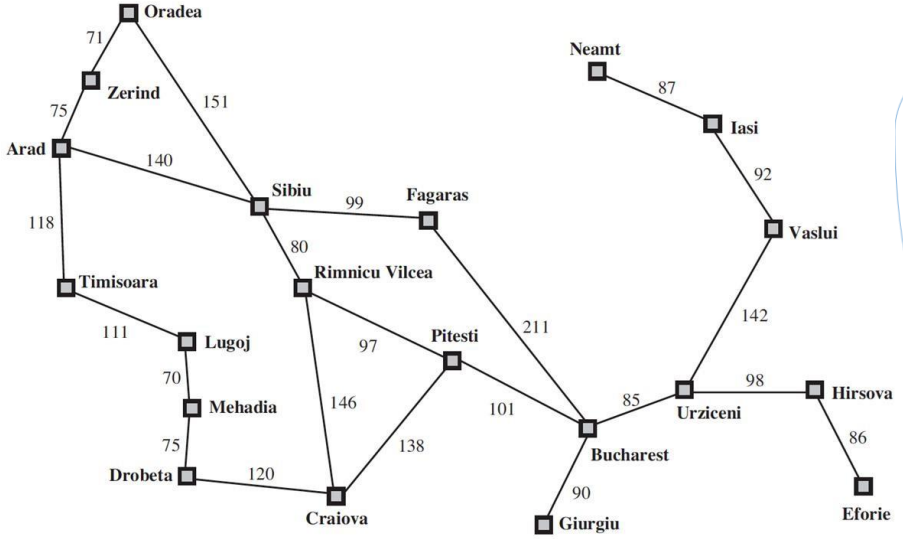
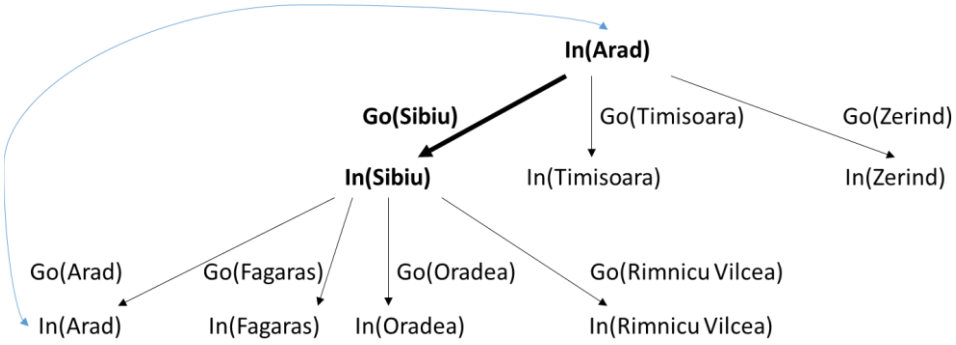
Coding Aspects

Graph-Search Algorithm

Augments the Tree-Search algorithm to solve redundancy by keeping track of states that are already visited called as **Explored Set**. **Only one copy of each state is maintained/stored.**





Graph Search Algorithms

function **Graph-Search** (problem, fringe) returns a solution, or failure

initialize the search space using the initial state of problems memory to store the visited fringe

closed an empty set

Insert(Make-Node(Initial-State[problem]), fringe)

fringe

loop if fringe is empty

do then return failure

node Remove-Front(fringe)

if the node contains a goal state

then return the corresponding solution

else

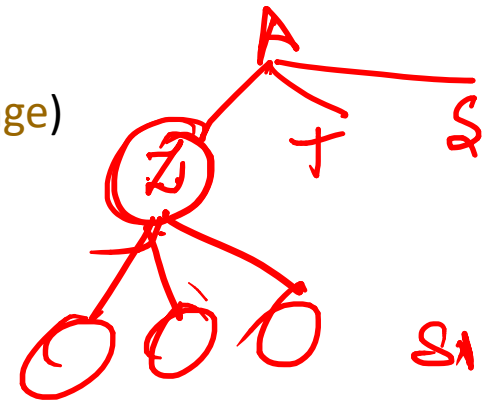
if the node is not in closed ie., not visited yet

Add the node to the closed set

Expand all the fringe of the node

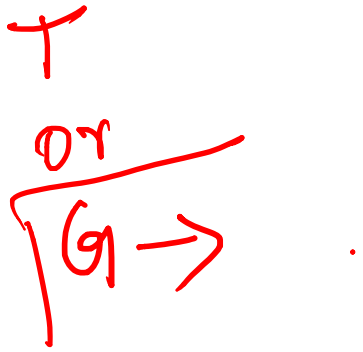
Add all expanded sorted successors into the fringe

end

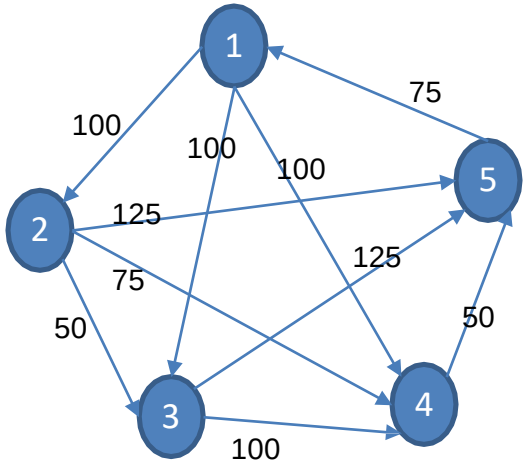


Informed Search

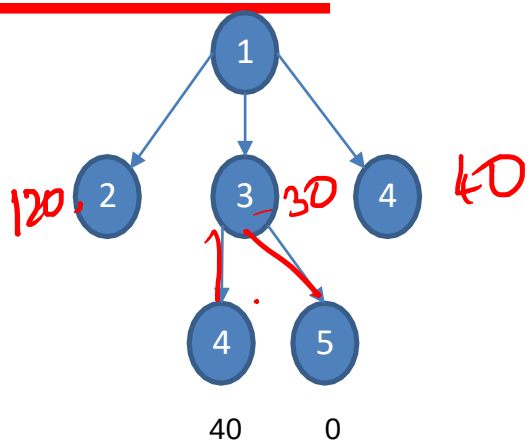
- Greedy Best First
- A*



Greedy Best First Search



h(n)

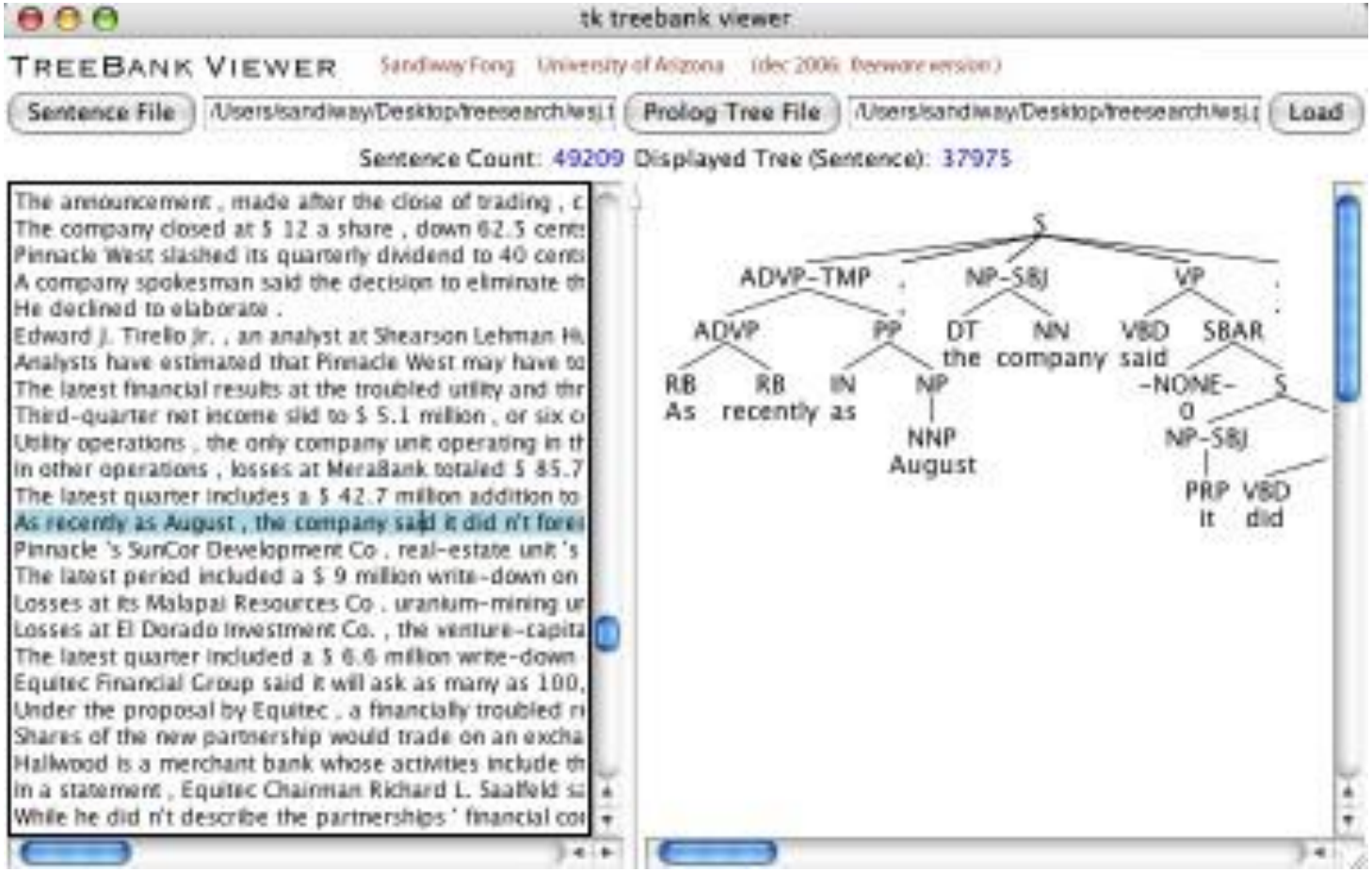


n	h(n)
1	60
2	120
3	30
4	40
5	0

(1)
(1 3) (1 4) (1 2)
(1 3 5) (1 3 4)

C(1-3-5) = 100 + 125 =225
Expanded : 2
Generated : 6
Max Queue Length : 3

Case Study – 1 Search in Treebanks

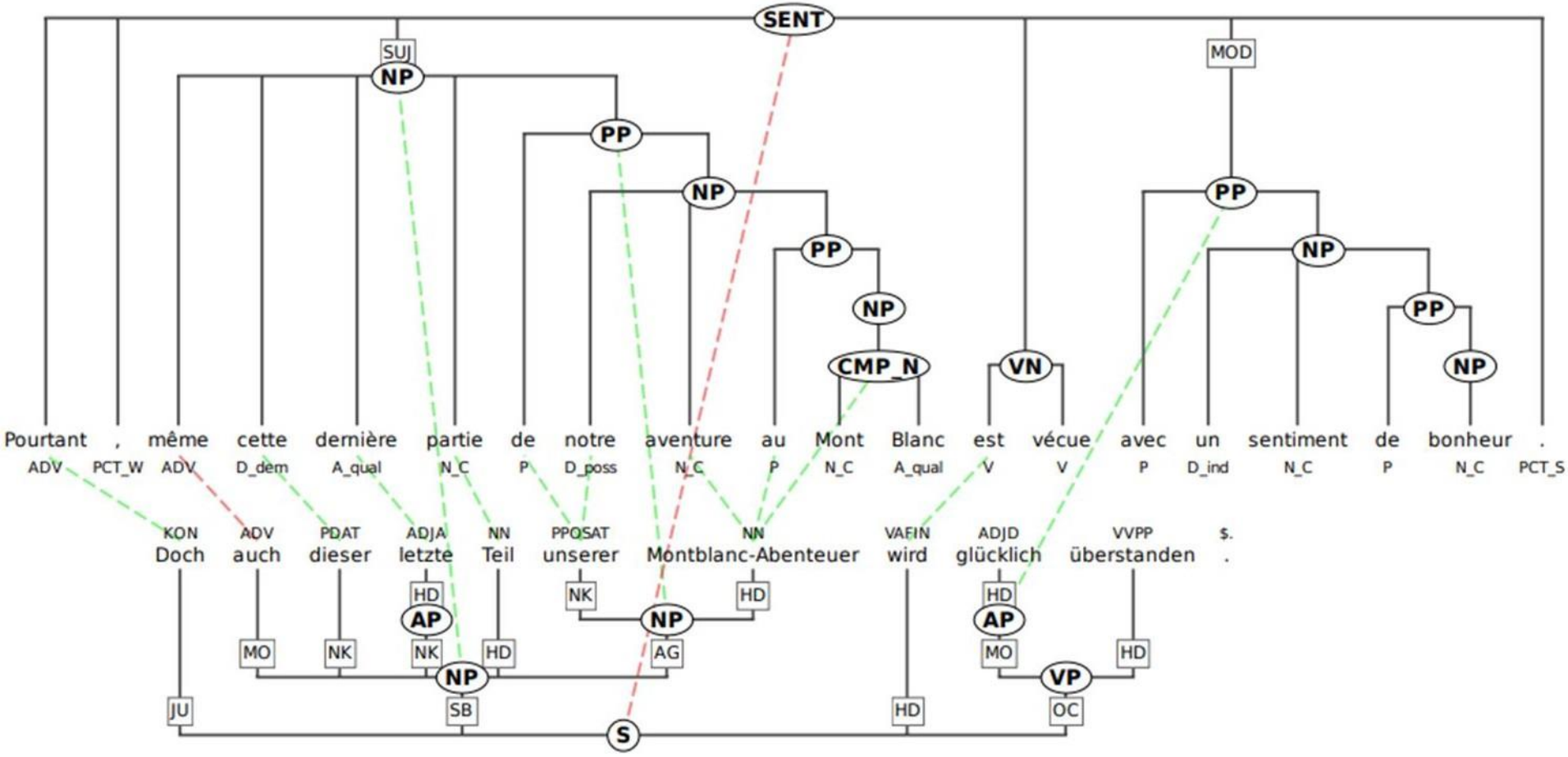


Source Credit :

https://catalog.ldc.upenn.edu/docs/LDC95T7/cl93.html

https://ufal.mff.cuni.cz/pdt3.5

Case Study – 1 Search in Treebanks

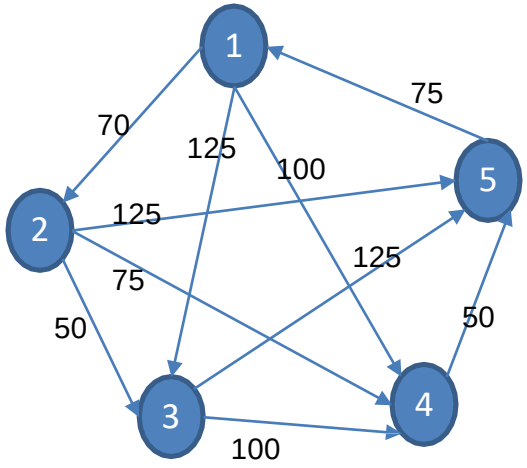


Source Credit :

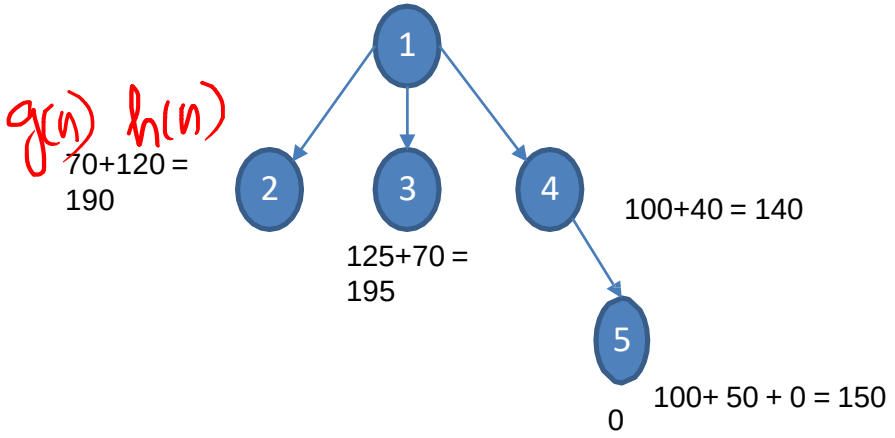
https://catalog.ldc.upenn.edu/docs/LDC95T7/cl93.html

https://ufal.mff.cuni.cz/pdt3.5

A* Search



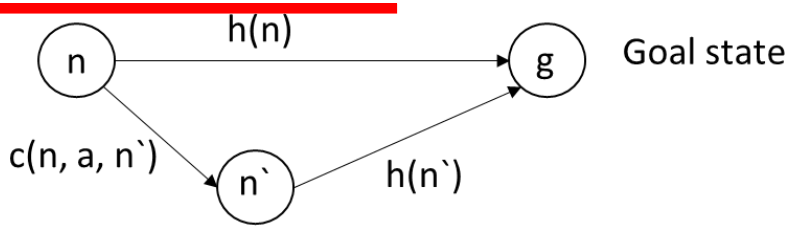
n	h(n)
1	60
2	120
3	70
4	40
5	0



(1)
(1 4) (1 2) (1 3)
(1 4 5) (1 2) (1 3)

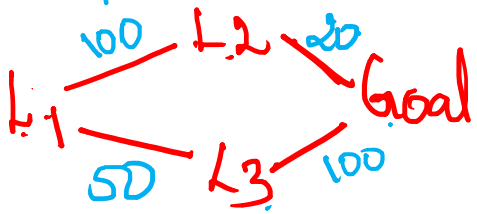
C(1-4-5) = 100 + 150 =150
Expanded : 2
Generated : 5
Max Queue Length : 3

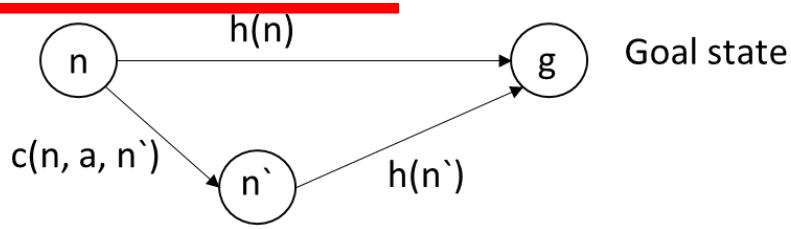
A* Search



A* Search

actual pathcost → $h^*(L)$





AI_analyst	
	h(L)
L2	50 ✓
L3	30

L.H.S

$h_{G_1}(L_2)$ < $h^*_{G_1}(L_2)$

R.H.S

less informed

$h_{G_1}(L_2)$ ↓ 50 overestimated

$h^*_{G_1}(L_2)$ ↓ 20 → more informed w.r.t environment

not accept overestimate

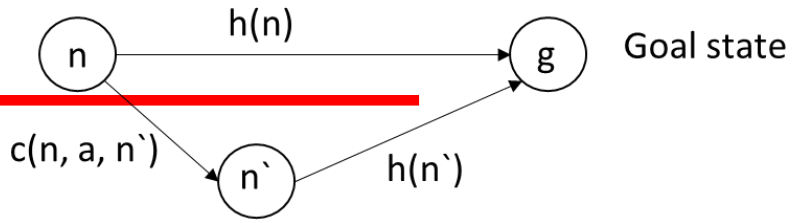
$h_{G_1}(L_3)$ < $h^*_{G_1}(L_3)$

underestimated — 30 — less

100 = → more

accept ✓

A* Search



Optimal on condition

h(n) must satisfies two conditions:

- Admissible Heuristic – one that never overestimates the cost to reach the goal
- Consistency – A heuristic is consistent if for every node n and every successor node n` of n generated by action a, h(n) <= c(n, a, n`) + h(n`)

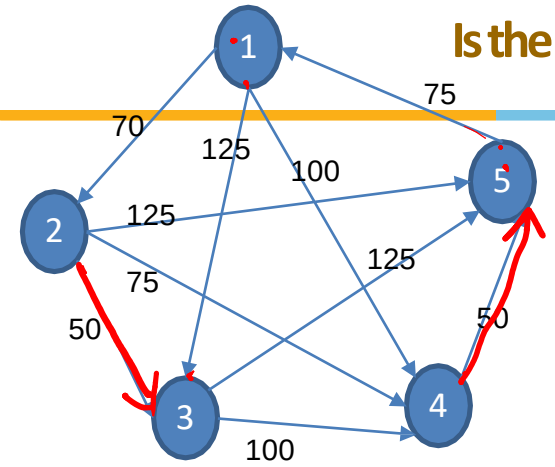
Complete

- If the number of nodes with cost <=C* is finite
- If the branching factor is finite
- A* expands no nodes with f(n) > C*, known as pruning

Time Complexity - $G(b^{\Delta})$ where the absolute error $\Delta = h^* - h$

A* Search

1-3 → P_1 → 1-3 (125)
P_2 → 1-2-3 (120)



Is the heuristic designed leads to optimal solution?

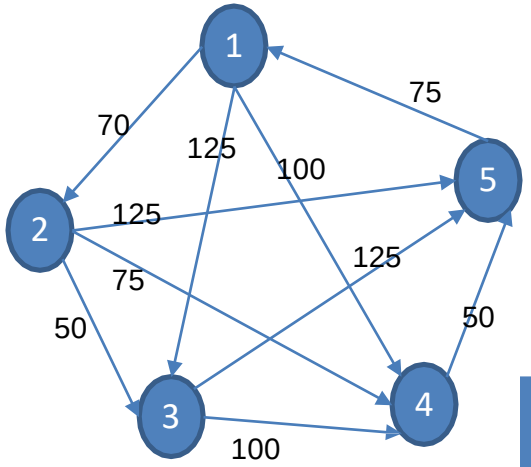
Assuming **node 3** as goal, taking only sample edges per node below is checked for consistency

	Best Path	n	h(n)	Is Admissible? h(n) <= h*(n)	Is Consistent? For every arc (i,j): h(i) <= g(i,j) + h(j)
125	1-2-3	1	80	80 ≤ 125 T → Yes	
50	2-3	2	60	60 ≤ 50 F → NO	
0	0	3	0		
245	4-(5)-1-2-3	4	200	200 ≤ 245 T yes	
195	5-1-2-3	5	190	190 ≤ 195 T yes	

A* Search

innovate achieve lead

Is the heuristic designed leads to optimal solution?

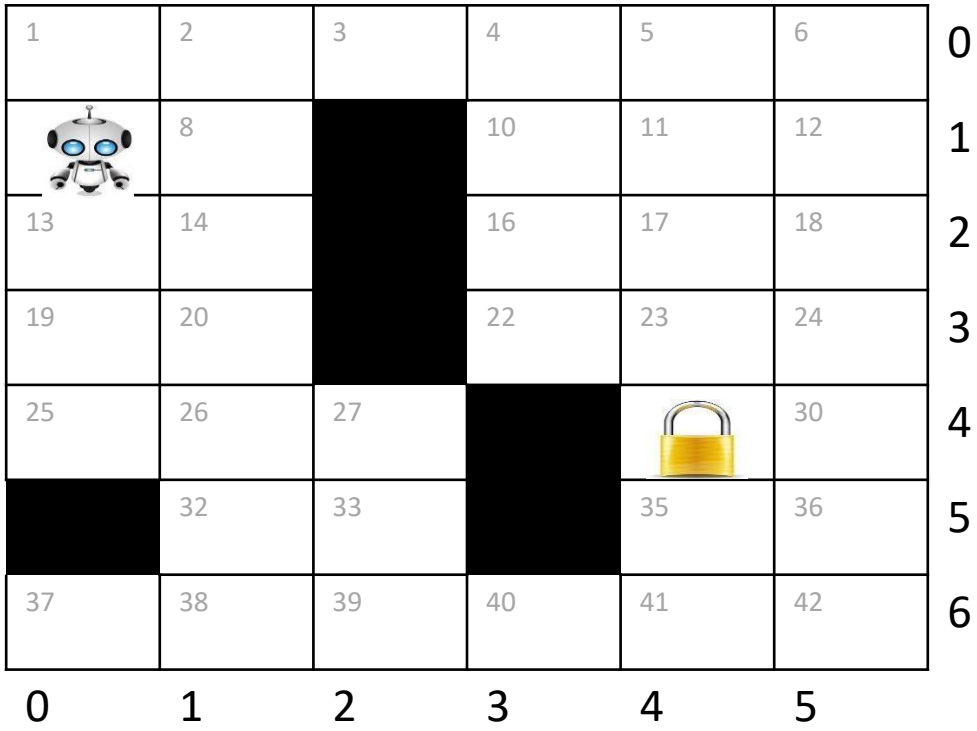


Assuming node 3 as goal, taking only sample edges per node below is checked for consistency

n	h(n)	Is Admissible? h(n) <= h*(n)	Is Consistent? For every arc (i,j): h(i) <= g(i,j) + h(j)
1	80	Y	N (5→1) : 190<=155
2	60	N	Y (1→2) : 80<=130
3	0	Y	
4	200	Y	Y (1→4) : 80<=300 Y (2→4) : 60<=275
5	190	Y	Y (2→5) : 60<=315 Y (4→5) : 200<=240

Path finding Robot – Sample Planning Agent Design

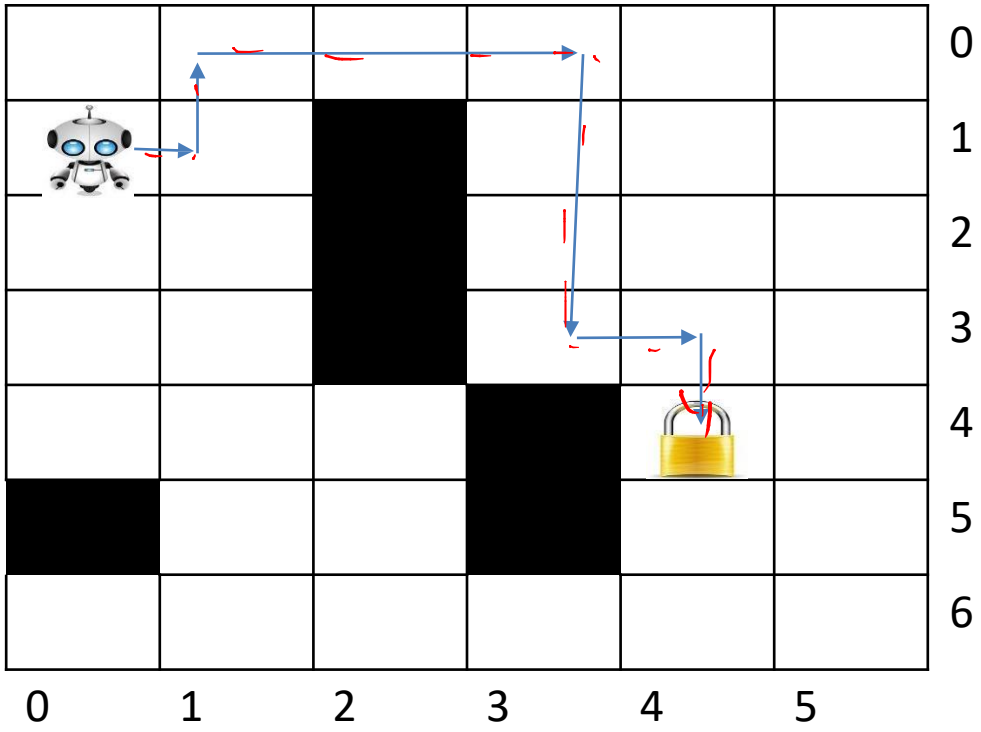
Successor Function Design



N-W-E-S

A*

Demo



Required Reading: AIMA - Chapter #1, 2, 3.1

Thank You for all your Attention

Note : Some of the slides are adopted from AIMA TB materials