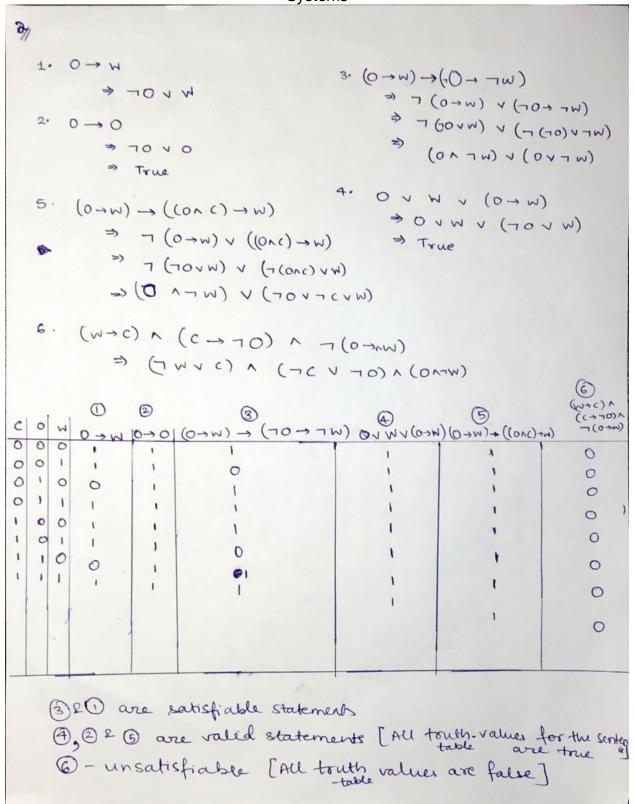
```
- Rainy - Pleasant
     Rainy - cloudy 1 - Pleasant
     Pleasant V Cloudy - Hiking
     Hiking -> Happy
Step 2 Replacing "-"
    7 (7 Rainy) V Pleasant
     T Rainy v (woudy 1 - Pleasant)
     7 (Pleasant v cloudy) v Hiking
      Thiking V Happy
Step 3
     Rainy V Pleasant
      TRainy v (cloudy 1 - Pleasant)
      (T Pleasant 1 T Cloudy) V Hiking
        7 Hiking V Happy
   3 7R V (C N 7P)
    3 (7P 17C) VG
       79 V H
```

we prove by contradiction, by asserting the clauses of premise I the negation of the conclusion 1 RVP (2) -1R V C Premise & by resolution of the statements 3 7R V-P on the previous eide a GV-P (5) 9 V 7 C (6) 7GVH a)/ let today not be Rainy, i.e., TR (1) ⇒ P adding ¬R to (1)
(8) ⇒ ¬R adding (1) to (2) Hence, today is not rainy and we cannot prove by contradiction b) Let "not Happy", i.e., TH (B) H Adding (2) to (6) Hence, our assumption contradicts (3) and by proof by contradiction I am happy c) Let today not be good for hiking, ie., 7 4 9 7P adding 74 to D (10) R adding 9 to 1) (1) c adding (1) to (2) Our assumption contradicts (12) and hence, by proof by contradiction, today is good for hiking



3 is not valid when old is false & wise is true 1 is not satisfiable / not valid when old is true & wise is false

```
3/
       (ats(x): x is a cat
        Animal(x): x is a animal
         \forall x : (ats(x) \rightarrow Animal(x)
    2.
         ∃x ∃y Animal (x) ~ Afraid (x,y) → Run (x,y) V Hide(x,y)
    3.
          Fx Fy cat(x) 1 (arky) -> Afraid(x,y)
          Fx Fy Cat(x) A Dog(y) -> Afraid (x,y)
         (at (Louie)
        Dog (Jake)
    6.
          ∃x ∃y Animal (x) A Hide(x,y) -> 7 Seen(x)
     J.
          Seen (Louice)
```

```
CNF form corresponding to the rules
 1. 7 (ats(x) V Animal(x)
 2. 7 Animal (x) V - Afraid (x,y) V Run (x,y) V Hide(x,y)
 3. T Cat (x) V T (ar (y) V Afraid (x, y)
 4. 7 Cat(x) v 7 Dog (y) v Afraid (x, y)
 5. Cat (Louie)
 6. Dog (Jake)
 7 Animal (2) V 7 Hide (x,y) V 7 Seen(2)
 8. Seen (Louie)
Poroof by contrdiction
   Assumption: 7 Run (Louie, jake)
> Substitute for in 2 7 Afraid (Louie, jake) V Hide (Louie, jake)
> substitute 69 in 7
     7 Animal (Louie) V - Seen (Louie) V - Afraid (Louie, Jake)
-> Substitute (6) in 4
     7 Animal (Louie) V 7 Seen (Louie) V 7 Cat (Louie) V 7 Dogijaki)
-> substitute (1) in 5
     7 Animal (Louie) V → Seen (Louie) V → Dog (jake) → (2)
-) Substitute (2) in 6
       TAnimal (louie) V - Seen (Louie)
   Substitue (B) in 8
        - Animal (louis) - (14)
```

→ substitute (1) in 1

¬ cat (Louie) — (15) However, in 5 we get (at (coine).

Since, 5 and (5) are a condradiction, it can be proved that Louis is running from jake

4.

```
Desktop — gprolog — 80×24
[| ?- setof(X, grandchild(X, elizabeth), List).
List = [beautrice, eugenie, harry, james, louise, peter, william, zara]
yes
[| ?- setof(X, brotherinlaw(X, diana), List).
                                                                                  ]
[] ?- setof(X, greatgrandparent(X, zara), List).
                                                                                  ]
List = [george, mum]
[| ?- setof(X, ancestor(X, eugenie), List).
List = [andrew,elizabeth,george,mum,philip,sarah]
yes
?- setof(X, ancestor(X, eugenie), List).
List = [andrew,elizabeth,george,mum,philip,sarah]
yes
| ?-
```

An interesting point to note is brother-in-law of Diana is "no" because we follow the simple definition of sibling-in-law as stated in the question. A brother-in-law or sister-in-law is defined as sisters spouse or brothers spouse. However, since Diana has no brother-in-laws as per our definition, "no" is returned.

```
5/
(i) Action (move (x, y, r),
              Precondition: Robot (rob) ^ At (robjex, r) A Room(r)
                              ~ Location (x, r) ^ Location(y, r)
              Effect: TAt (robot, x, r) At (robot, y, r))
(ii) Action (Rush (b, x, y, r),
            Precondition: Box (b) ^ Room (r) ^ At (b, x, r)^
                     Robot(rob) Location (x, r) ~ Location (y, r)
             Effect: TAt (b, x, r) ^ At (b, y, r))
(iii) Action (Twonon (s),
               Precondition: Switch(s) A Room (r) At (s,T)
                               1 Ton (s) 1 Robot (rob) 1 At (rob)
               Effect = Off(s))
(IV) Action (Turn Off (S) 5
                Perecondition: Switch (s) A Room (r) A At(s, r)
                                On (s) A Robot (rob) A At (rob, r)
                Effect: Off (s))
6)
   Init (Robot (rob) 1 Room (Ri) 1 Room (R2) 1 Room (R3)1
           Box (Bi) 1 Box (B2) 1 Box (B3) 1 Room (Hallway)
           At (rob, R2) ^ At (B1, R1) ^ At (B2, R1) ^ At (B2, R3))
```

```
4
    Goal (At (B1, R3):
       Action (Move (start, start, R2)
                Precondition: Robot (rob) ^ Room (R2) ^ At (rob, Start, R2) ^
                           Location (start, R2) ^ Location (D2, R2)
                Effect: ¬At (rob, start, R2) ~ At (rob, D2, R2)).
     Action (move (D2, D1, Halloway)
               Precondition: Robot (80b) ^ Room (Hallway) 1 At (rob, P2,
                               ^ Location (B2, Hallway) A Location (D, Hallway)
               Effect: - At (rob, D2, Hallway) , At (rob, D, Hallway)
     Action (move (Di, &x, , Ri),
               Precondition: Robot (920b) ^ Room (R1) ^ At(10b, D13
                                1 Location (D, R,) 1 Location (x, R))
                 Effect: - At (rob, D, g, R,) At (rob, x, g, R,))
    Action ( Push (B, 2, Din Ri) ,
               Psecondition: Robot (rob) ^ Room (R,) ^ At (,x,R)
                     ^ Box (Bi) ^ Location (x, , Ri) ^ Location (Di, Ri))
                Effect: TAt ( R, R, ) A At ( D, D, R, ))
   Action ( Push (B, , D, , D3, Halleway),
              Perecondition: Robot (rob) ~ Room (Hallway) ~ At (B), D, holling
                   1 Box (B) 1 Location (D; Hallway) 1 Location (Ds. Hallway)
               Effect: - At (B, D, Hallway) A At (B, D3, Hallway)
  Action (Push (B1, D3, End R3),
               Precondition: Box (B,) 1 Robot (rob) 1 Room(R3) 1 At (B, D3, R3)
                          ^ Location (03, R3) ^ Location ( R3)
               Effect: - At (B, D3, R3) At (B, 80, R3))
```

-> We represent the rooms using the notation of 'R' subscripted by room numbers. Eg (R, g R2 g R3 f Whe represent the boxes using the notation of 'B' subscripted by box numbers. Eg [ B, g B2 g B3} we represent the doors to the rooms as 'D' subscripted by the room number , i.e., D, is the door to R, & D2 to R2 and D3 to R3. in the first step, the robot moves from the start position in Room R2 to the position D2 in R2. As stated in the question D2 is in R2 and the hallway " In the second step, the robot moves from D2 which is at R2 and the hallway to D2 in the hallway again. The constraint 1sthat we can move from position & to position y within the room only. > In the 3rd step, the robot moves from position D, in the room to the box location in the room. -> And so, we continue the process of moving the box & from Room R, to Room Rz in a similar fashion of the branching factor for this version of the problem coulding 3 \* 3 + 2 \* 3 + 1 \* 3 = 18 3 boxes 2 3 rooms 2 2 turn off lon action action per room 3 rooms (2 rooms + hallway) If the problem were for knooms & m boxes the problem and could be represented as m\*k + 2\* K+1\*k) = [m\*k+3\*k]