

CSE422 : ARTIFICIAL INTELLIGENCE

STRUCTURE OF AGENTS

BY

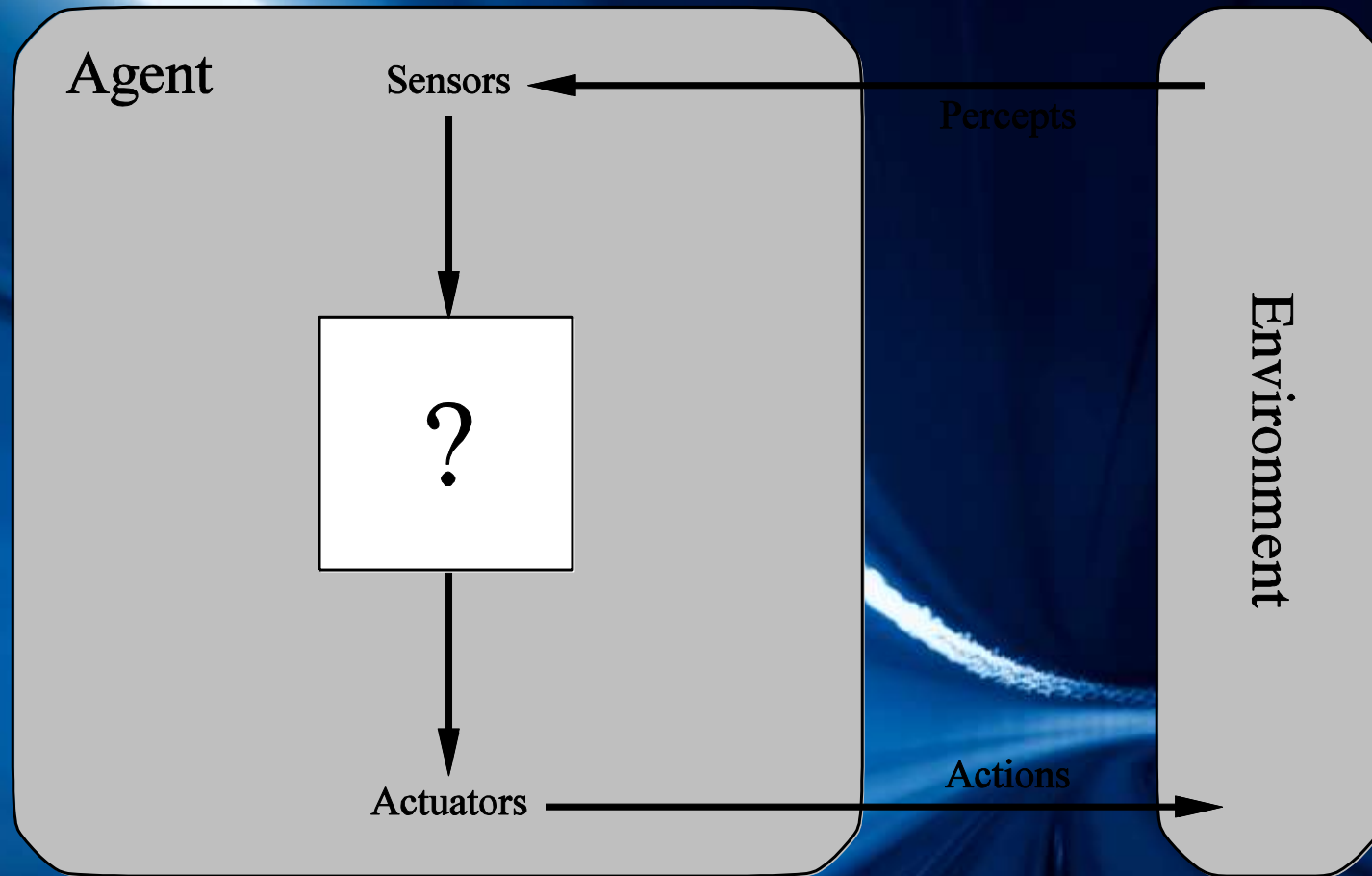
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How do you design an intelligent agent?

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- ▶ Definition: An **intelligent agent** perceives its environment via **sensors** and acts rationally upon that environment with its **actuators**.
- ▶ A discrete agent receives **percepts** one at a time, and maps this percept sequence to a sequence of discrete **actions**.
- ▶ Properties
 - ▶ Autonomous
 - ▶ Reactive to the environment
 - ▶ Pro-active (goal-directed)
 - ▶ Interacts with other agents via the environment

AGENTS



Sensors/Percepts and Actuators/Actions

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► Humans

- Sensors: Eyes (vision), ears (hearing), skin (touch), tongue (gustation), nose (olfaction), neuromuscular system (proprioception)
- Percepts:
 - At the lowest level – electrical signals from these sensors
 - After preprocessing – objects in the visual field (location, textures, colors, ...), auditory streams (pitch, loudness, direction), ...
- Actuators: limbs, digits, eyes, tongue, ...
- Actions: lift a finger, turn left, walk, run, carry an object, ...
- ❖ **The Point:** percepts and actions need to be carefully defined, possibly at different levels of abstraction

TYPES OF AGENT

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▶ **Table-driven agents**

- ▶ use a percept sequence/action table in memory to find the next action. They are implemented by a (large) **lookup table**.

▶ **Simple reflex agents**

- ▶ are based on **condition-action rules**, implemented with an appropriate production system. They are stateless devices which do not have memory of past world states.

▶ **Agents with memory(model/knowledge)**

- ▶ have **internal state**, which is used to keep track of past states of the world.

▶ **Agents with goals**

- ▶ are agents that, in addition to state information, have **goal information** that describes desirable situations. Agents of this kind take future events into consideration.

▶ **Utility-based agents**

- ▶ base their decisions on **classic axiomatic utility theory** in order to act rationally.

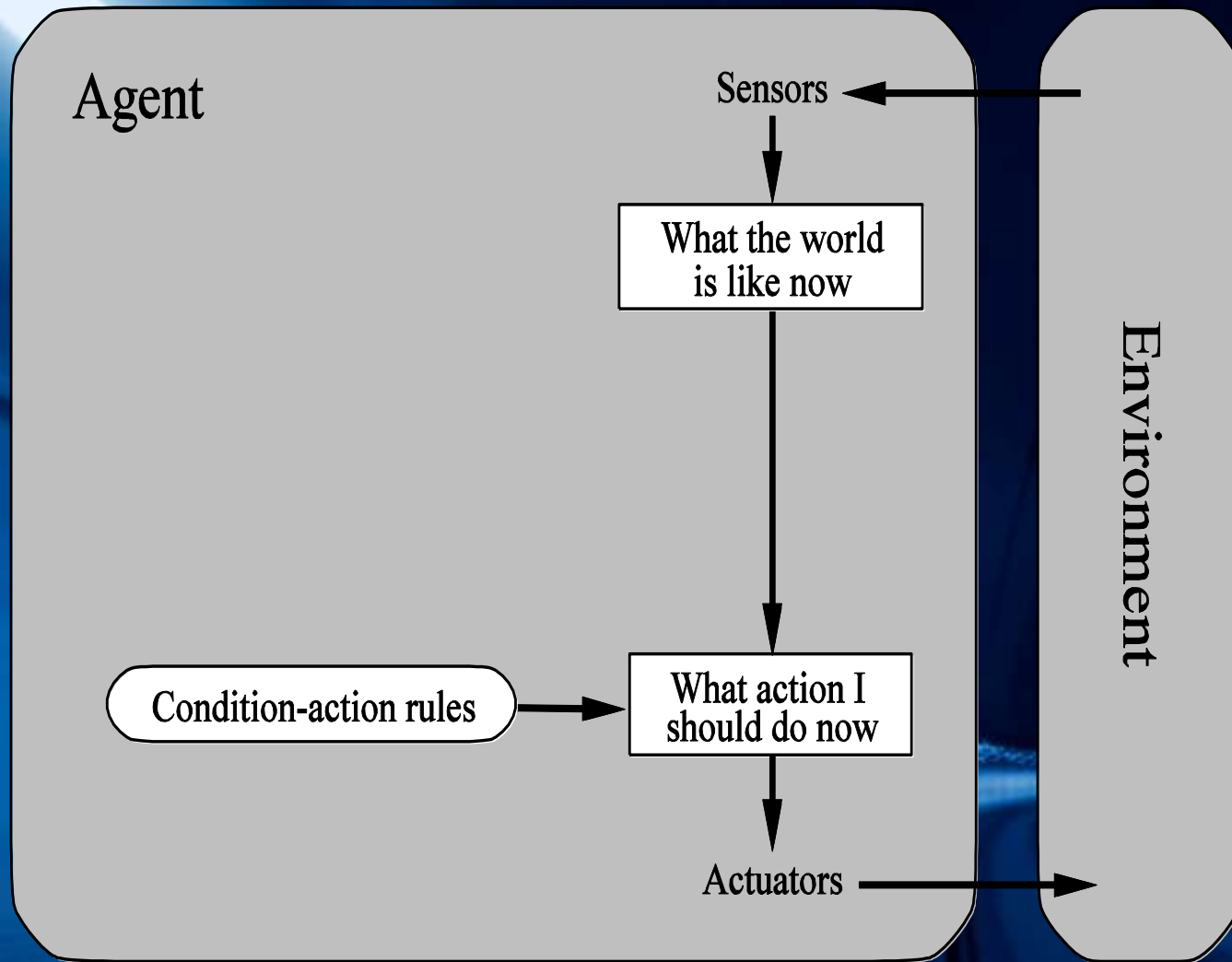
Table-driven agents

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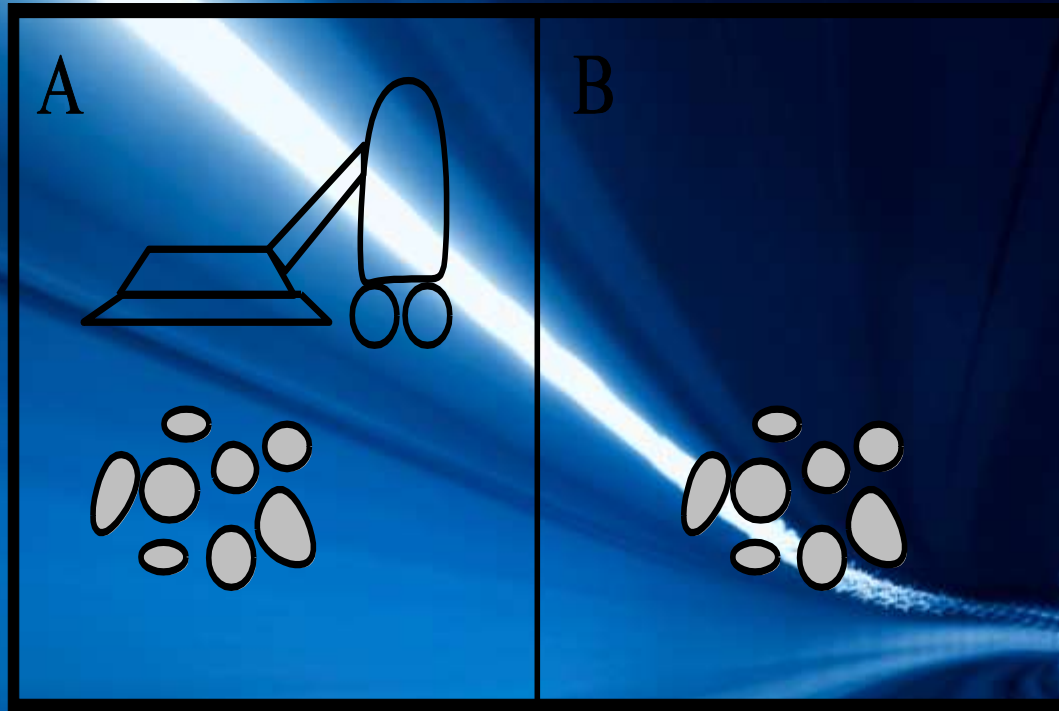
- ▶ **Table lookup** of percept-action pairs mapping from every possible perceived state to the optimal action for that state
- ▶ **Problems**
 - ▶ Too big to generate and to store (Chess has about 10^{150} states, for example)
 - ▶ No agent could ever learn all the right table entries from its experience
 - ▶ No guidance about how to fill in the table entries
 - ▶ Not adaptive to changes in the environment; requires entire table to be updated if changes occur
 - ▶ Looping: Can't make actions conditional on previous actions/states

Simple reflex agents

- ▶ Immediate or spontaneous action
- ▶ Do not check past record
- ▶ Based on current state
- ▶ Based on If-Then rule
- ▶ Problems
 - ▶ Too big table to generate and to store
 - ▶ Do not work for partially observable environment
 - ▶ Do not involve multiple condition
 - ▶ No knowledge of non-perceptual parts of state
 - ▶ Not adaptive to environment change; requires collection of rules to be updated if changes occur
 - ▶ Can't make actions conditional on previous state



Architecture of Simple reflex agent architecture



Example:
Vacuum Cleaner

Simple Function

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Percept Sequence

[A, Clean]

[A, Dirty]

[B, Clean]

[B, Dirty]

[A, Clean], [A, Clean]

[A, Clean], [A, dirty]

...

...

[A, Clean], [A, Clean], [A, Dirty]

Action

Right

Suck

Left

Suck

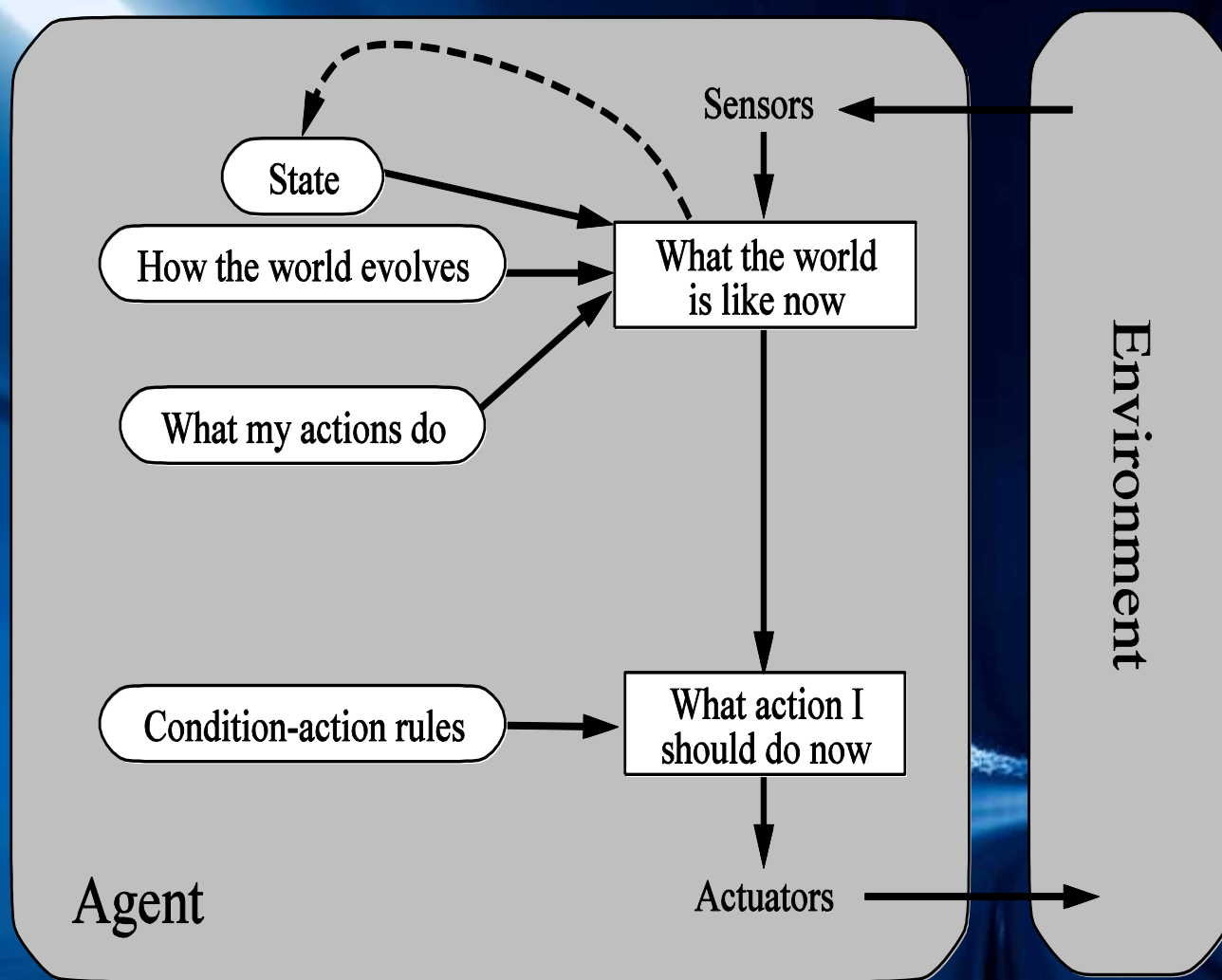
Right

Suck

Suck

Model-based Agents

- ▶ Knowledge based
- ▶ Store percept history
- ▶ Partially observable environment
- ▶ Adaptive ability to environment change



Architecture
for a model-
based agent

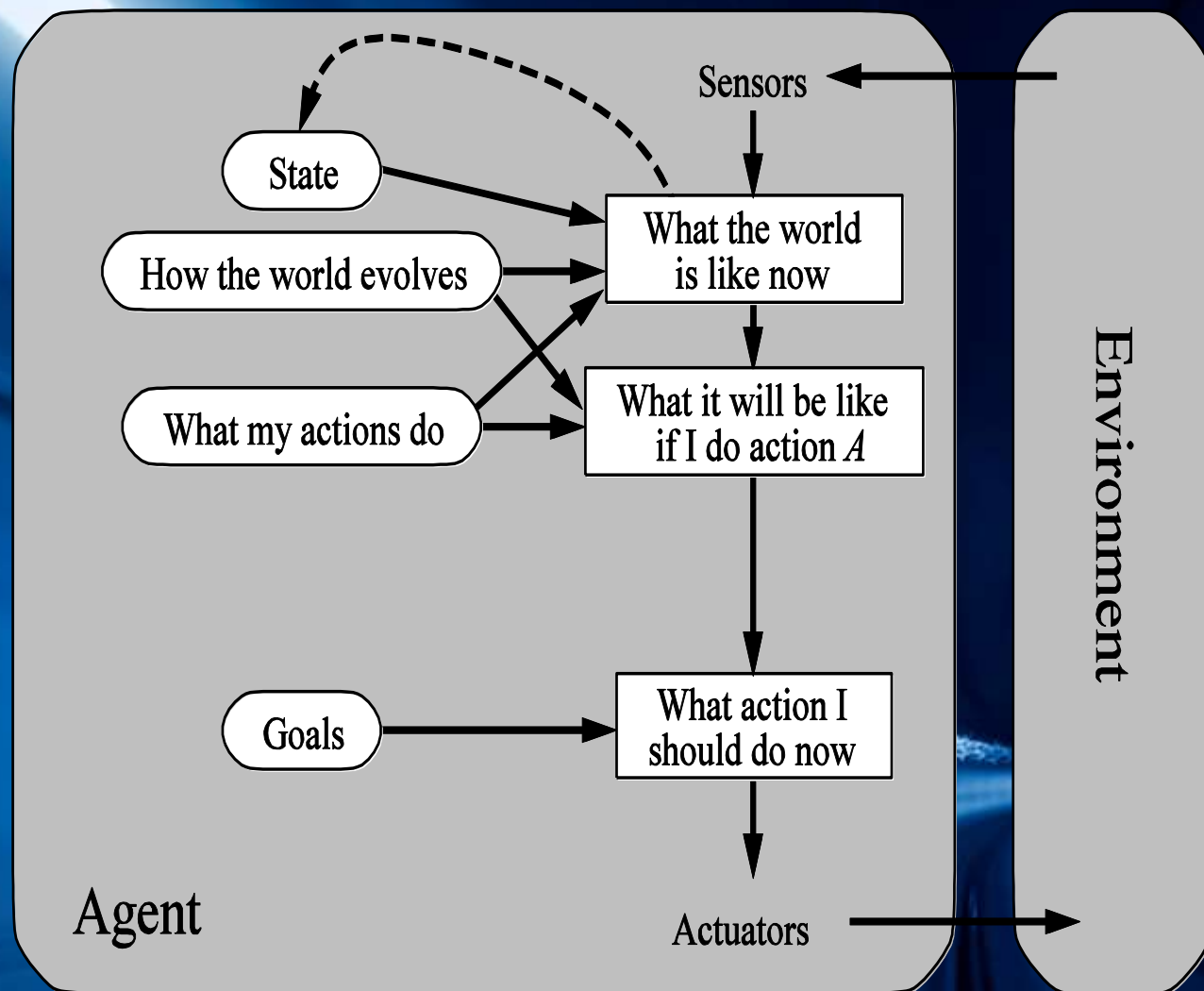
Automated taxi driving system

- ▶ **Percepts:** Video, sonar, speedometer, odometer, engine sensors, keyboard input, microphone, GPS, ...
- ▶ **Actions:** Steer, accelerate, brake, horn, speak/display, ...
- ▶ **Goals:** Maintain safety, reach destination, maximize profits (fuel, tire wear), obey laws, provide passenger comfort, ...
- ▶ **Environment:** Urban streets, freeways, traffic, pedestrians, weather, customers, ...

Goal-based agent

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- ▶ Expansion of model based agent
- ▶ Choose actions so as to achieve a desired goal
- ▶ Keeping track of the current state and past state are not enough – need to add goals to decide which situations are good
- ▶ Searching and Planning
- ▶ **Deliberative** instead of **reactive**.
- ▶ May have to consider long sequences of possible actions before deciding if goal is achieved – involves consideration of the future, “*what will happen if I do...?*”



Architecture for goal-based agent

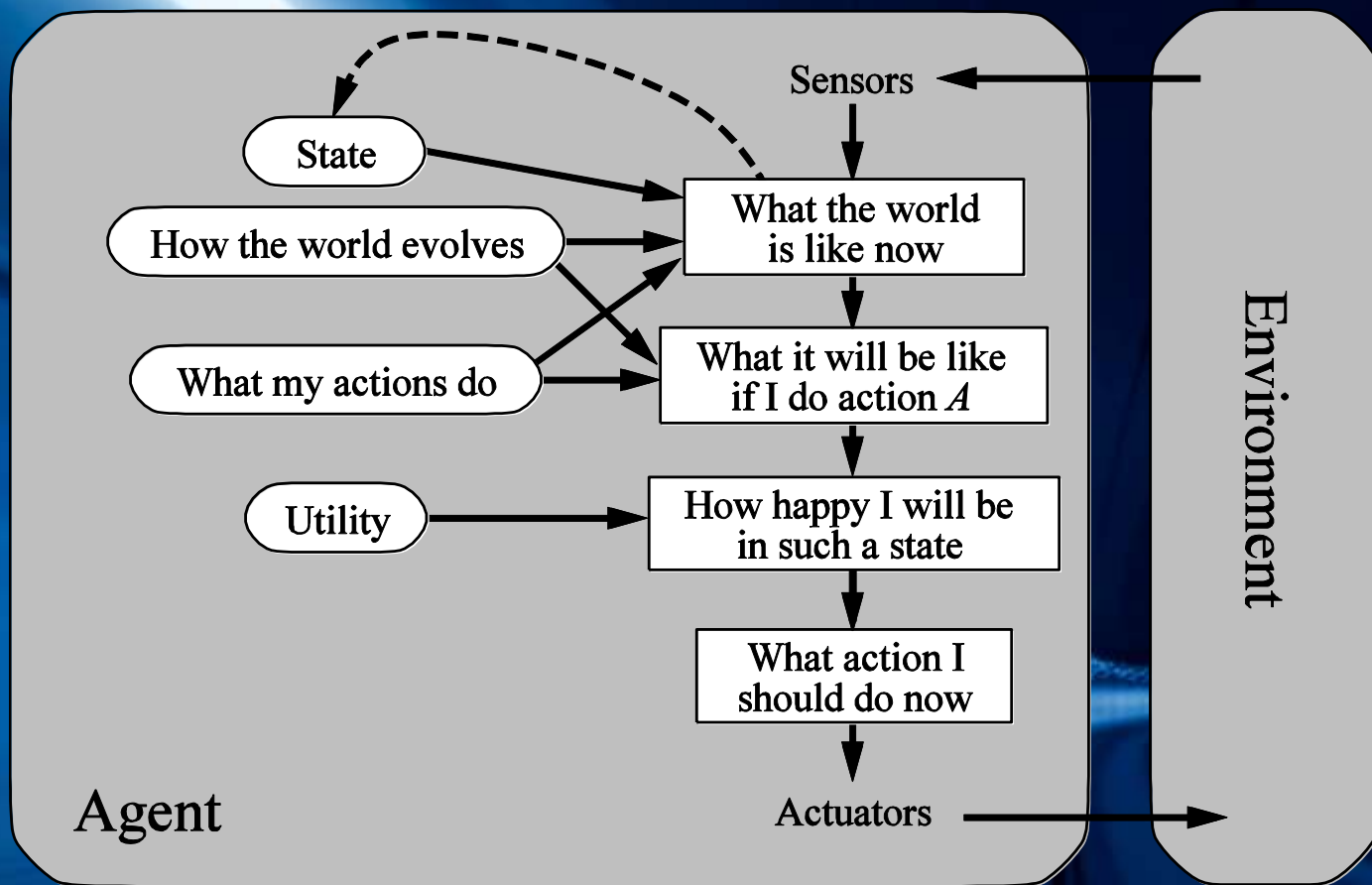


G+ Robot by Alibaba Company

Utility-based agents

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- ▶ When there are multiple possible alternatives, how to decide which one is best?
- ▶ Focuses on utility or degree of happiness
- ▶ Utility function **U: State \rightarrow Reals** indicating a measure of success or happiness when at a given state
- ▶ Allows decisions comparing choice between conflicting goals, and choice between likelihood of success and importance of goal (if achievement is uncertain)
- ▶ **Example: Mars Lander on the surface of mars with obstacle in its way; utility function will direct it to choose best path for best output**



Architecture
for a complete
utility-based
agent

Thank You!