CSC2542
Representations for (Classical) Planning

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Acknowledgements

Some the slides used in this course are modifications of Dana Nau's lecture slides for the textbook *Automated Planning,* licensed under the Creative Commons Attribution-NonCommercial-ShareAlike License: http://creativecommons.org/licenses/by-nc-sa/2.0/

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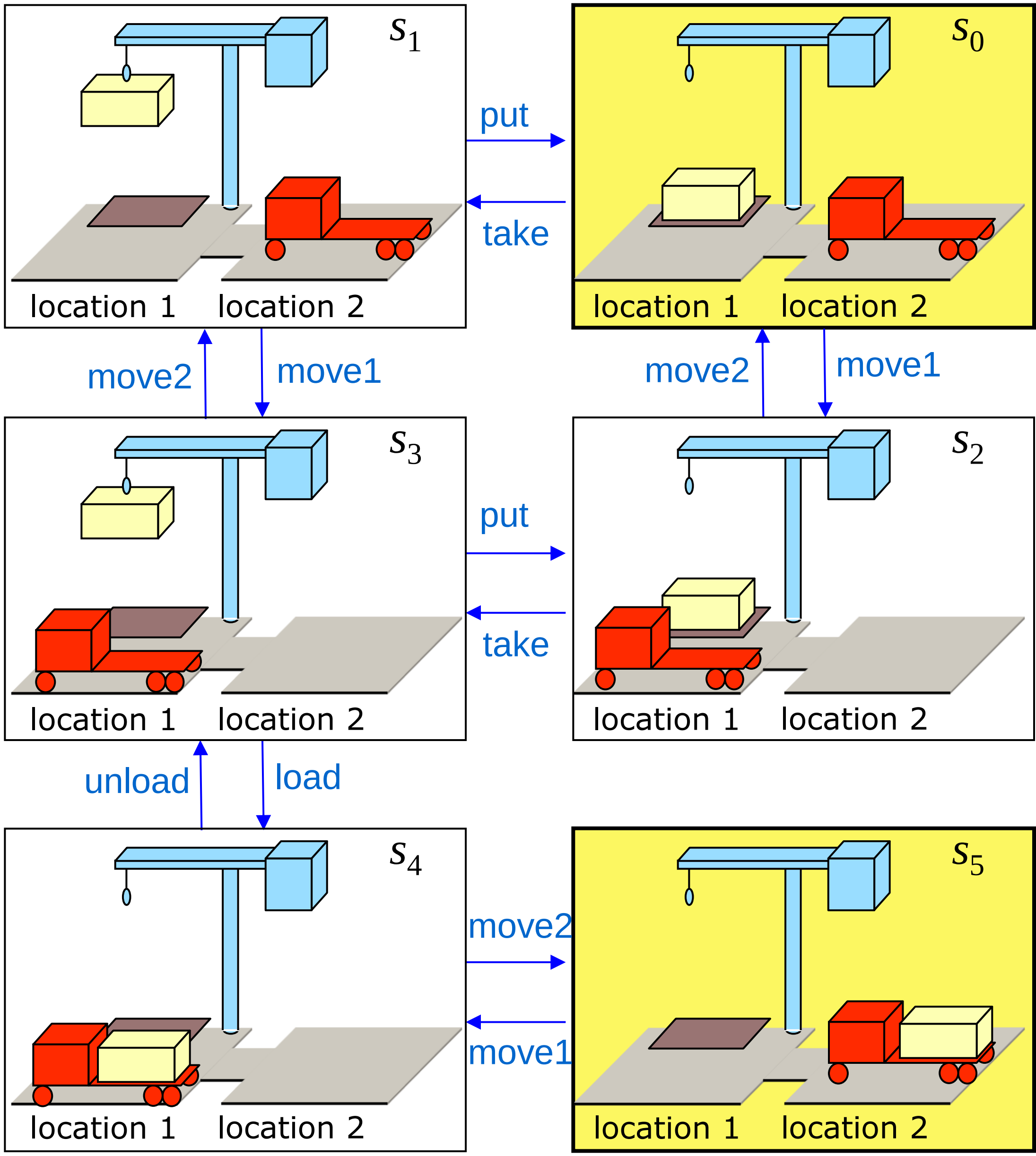
Recall: Planning Problem

$P = (\Sigma, s_0, G)$

Σ: System Description

s_0: Initial state(s)
E.g., Initial state = s_0

G: Objective
Goal state,
Set of goal states,
Set of tasks,
“trajectory” of states,
Objective function, …
E.g., Goal state = s_5



The Dock Worker Robots (DWR) domain

Further Recall:
System Description (as a state transition system)

$\Sigma = (S, A, E, \gamma)$

- S = {states}
- A = {actions}
- E = {exogenous events}
- State-transition function $\gamma : S \times (A \cup E) \rightarrow 2^S$

Example: Dock Workers Robots from previous slide

- $S = \{s_0, \ldots, s_5\}$
- A = {move1, move2, put, take, load, unload}
- $E = \{\}$
- γ: as captured by the arrows mapping states and actions to successor states

Representational Challenge

- How do we represent our planning problem is a way that supports exploration of the principles and practice of automated planning?

Approach:

- There isn't one answer.
- The [GNT04] proposes representations that are suitable for ***generating classical*** plans.

[GNT04] = Ghallab, Nau, Traverso, **Automated Planning: Theory and Practice**, 2004

Broad Perspective on Plan Representation

The right representation for the right objective.

Distinguish representation schemes for:

1. **studying the principles of planning** and related tasks.
2. **specifying planning domains**
3. **direct use within (classical) planners**

Summary: Broad Perspective

1. Studying the formal principles of planning and other related task

- (First-order) logical languages
  (e.g., situation calculus, *A* languages, event calculus, fluent calculus, PDL)

Properties:

- well-defined semantics, representational issues must be addressed in the language (not in the algorithm that interprets and manipulates them)
- excellent for study and proving properties. Not ideal for 3 below.

2. Specifying planning domains

- PDDL-n (PDDL2.1, PDDL2.2, PDDL3, ….)

Properties:

- (reasonably) well-defined semantics
- designed for input to planners – translate to an internal representation for specific planners. Translators exist for most state-of-the-art planners

3. Direct use within (classical) planners

- Classical representation (e.g., STRIPS)
- Set-theoretic representation (basis for rep'ns used w/ SAT solvers)
- State-variable representation (aka "*Finite Domain Repn' (FDR)*" *)(e.g., SAS, SAS+)

Variants of these exist for particular planners (e.g., SAT solvers, model checkers, etc.)

* [Helmert, AIJ 2009]

This Lecture:

1. Studying the formal principles of planning and other related task

- (First-order) logical languages
  (… calculus, PDL)

  Pro…
- w… dressed in the
  l… es them)
- e… elow.

2. Spec…

WILL COVER LATER

- PDDL-n (PDDL2.1, PDDL2.2, PDDL3, ….)

  Properties:
- (reasonably) well-defined semantics
- designed for input to planners – translate to an internal representation for specific planners. Translators exist for most state-of-the-art planners

3. Direct use within (classical) planners (what's in the text)

- Classical representation (e.g., STRIPS)
- Set-theoretic representation (basis for rep'ns used w/ SAT solvers)
- State-variable representation (aka "FDR") (e.g., SAS, SAS+)

  Variants of these exist for particular planners (e.g., SAT solvers, model checkers, etc.)

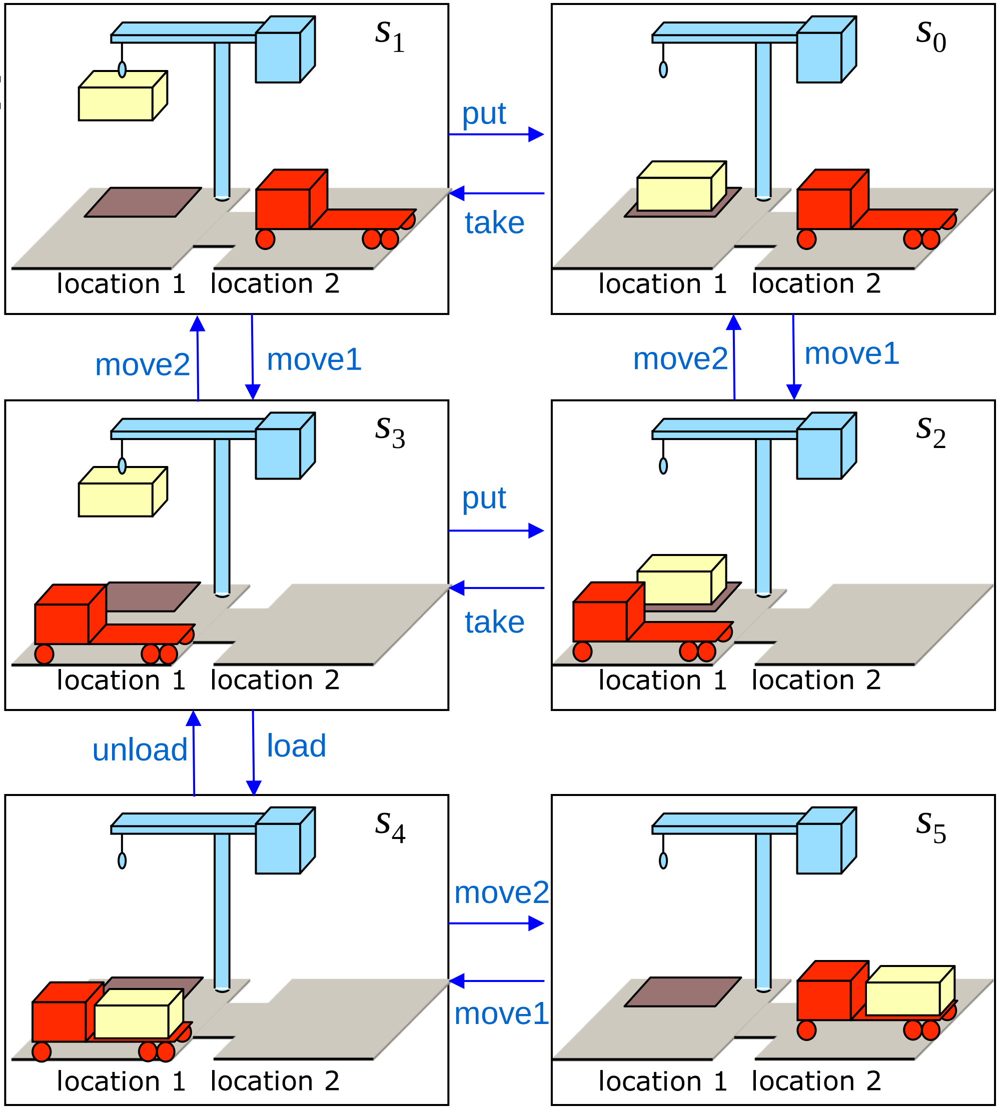
Outline

- Representation schemes for classical planning
    1. Classical representation
    2. Set-theoretic representation
    3. State-variable representation
- Examples: DWR and the Blocks World
- Comparisons

Quick Review of Classical Planning

8 restrictive assumptions req'd:

- A0: Finite
- A1: Fully observable
- A2: Deterministic
- A3: Static
- A4: Attainment goals
- A5: Sequential plans
- A6: Implicit time
- A7: Offline planning



Representation: Motivation for Approach

Default view:

- represent state explicitly
- represent actions as a transition system (e.g., as an incidence matrix)

Problem:

- explicit graph corresponding to transition system is huge
- direct manipulation of transition system is cumbersome

Solution:

Provide **compact representation** of transition system & induced graph

1. Explicate the structure of the "states"
   - e.g., states specified in terms of state variables
2. Represent actions not as transition system/incidence matrices but as functions (e.g., operators) specified in terms of the state variables
   - An action is applicable to a state when some state variables have certain values. When applicable, it will change the values of certain (other) state variables
3. To plan,
   - Just give the initial state
   - Use the operators to generate the other states as needed

Why is this more compact?

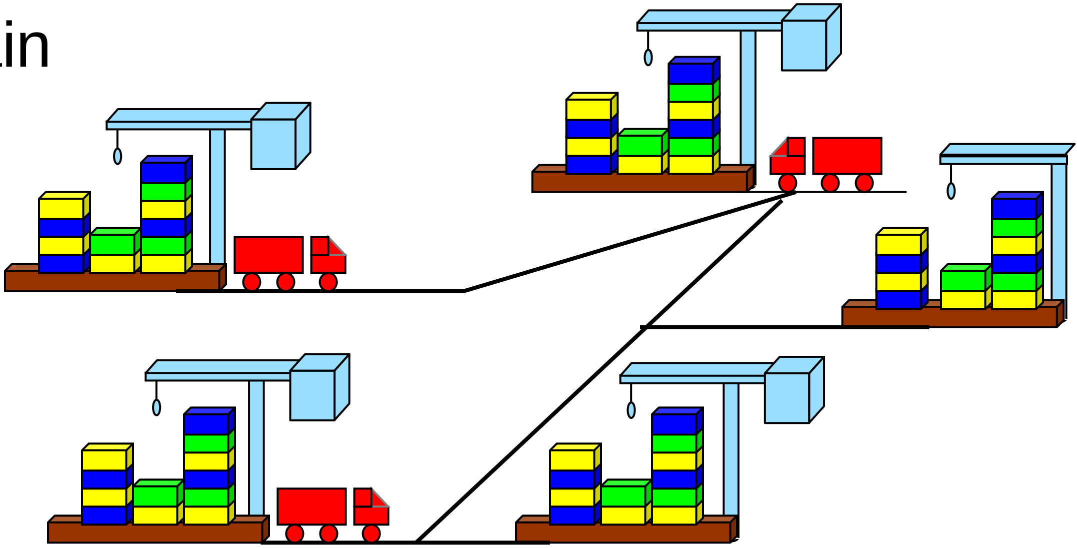
Why is this more compact than an explicit transition system?

- In an explicit transition system, actions are represented as state-to-state transitions. Each action will be represented by an incidence matrix of size |S|x|S|
- In the proposed model, actions are represented only in terms of state variables whose values they care about, and whose value they affect. *(It exploits the structure of the problem!)*
- Consider a state space of 1024 states. It can be represented by $\log_2 1024=10$ state variables. If an action needs variable v1 to be true and makes v7 to be false, it can be represented by just 2 bits (instead of a 1024x1024 matrix)
  - Of course, if the action has a complicated mapping from states to states, in the worst case the action rep will be just as large
  - <u>The assumption being made here is that the actions will have effects on a small number of state variables.</u>

1. Classical Representation

- Start with a *function-free* first-order language
  - Finitely many predicate symbols and constant symbols, but *no* function symbols

- Example: the DWR domain
  - Locations: l1, l2, …
  - Containers: c1, c2, …
  - Piles: p1, p2, …
  - Robot carts: r1, r2, …
  - Cranes: k1, k2, …



Quick review of terminology

- **Atom:** predicate symbol and args
  - Use these to represent both fixed and dynamic ("fluent") relations

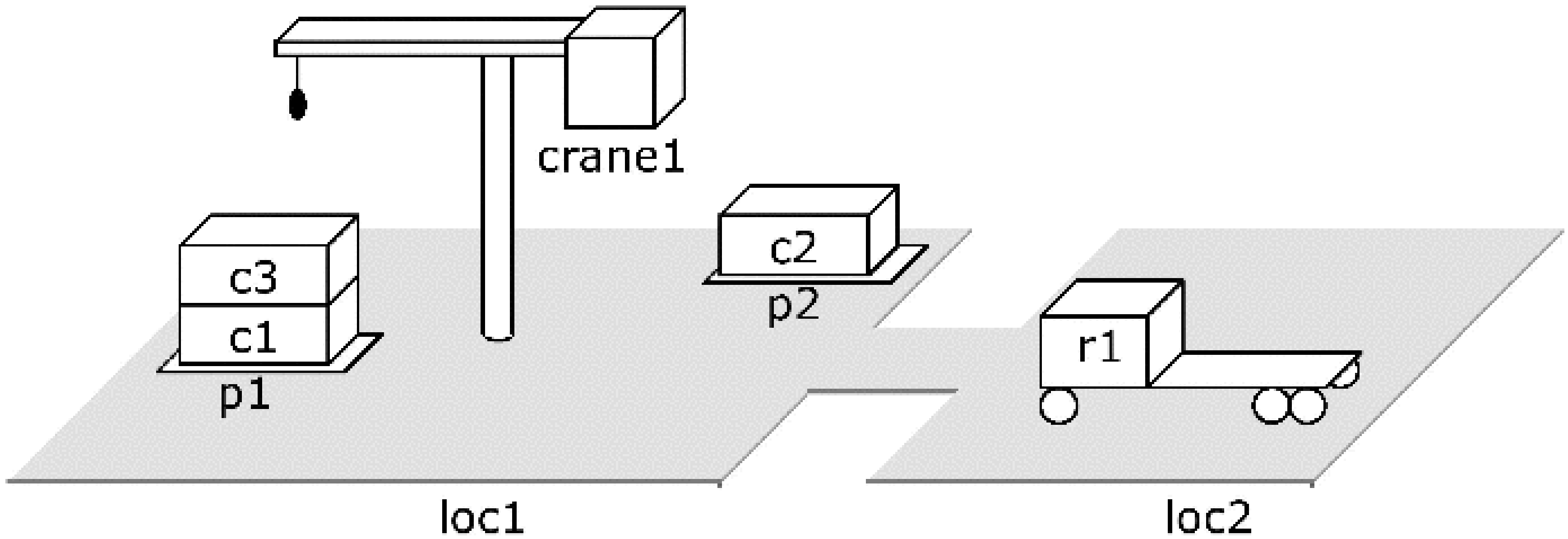
adjacent(*l*,*l'*)	attached(*p*,*l*)	belong(*k*,*l*)
occupied(*l*)	at(*r*,*l*)	
loaded(*r*,*c*)	unloaded(*r*)	
holding(*k*,*c*)	empty(*k*)	
in(*c*,*p*)	on(*c*,*c'*)	
top(*c*,*p*)	top(pallet,*p*)	

- **Ground** expression: contains no variable symbols - e.g., in(c1,p3)
- **Unground** expression: at least one variable symbol - e.g., in(c1,*x*)

- **Substitution:** $\theta = \{x_1 \leftarrow t_1,\ x_2 \leftarrow t_2,\ \ldots,\ x_n \leftarrow t_n\}$
  - Each x_i is a variable symbol; each t_i is a term
- **Instance** of *e*: result of applying a substitution θ to *e*
  - Replace variables of *e* simultaneously, not sequentially

States

- **State:** a **set** *s* of ground atoms
  - The atoms represent the things that are **true** in one of Σ's states
  - Only finitely many ground atoms, so only finitely many possible states



{attached(p1,loc1), in(c1,p1), in(c3,p1), top(c3,p1), on(c3,c1), on(c1,pallet), attached(p2,loc1), in(c2,p2), top(c2,p2), on(c2,pallet), belong(crane1,loc1), empty(crane1), adjacent(loc1,loc2), adjacent(loc2,loc1), at(r1,loc2), occupied(loc2), unloaded(r1)}.

Operators

- **Operator:** a triple o=(name(o), precond(o), effects(o))
  - name(o) is a syntactic expression of the form $n(x_1,\ldots,x_k)$
    - n: *operator symbol* - must be unique for each operator
    - $x_1,\ldots,x_k$: variable symbols (parameters)
      - must include every variable symbol in o
  - precond(o): *preconditions*
    - literals that must be true in order to use the operator
  - effects(o): *effects*
    - literals the operator will make true

take(k, l, c, d, p)

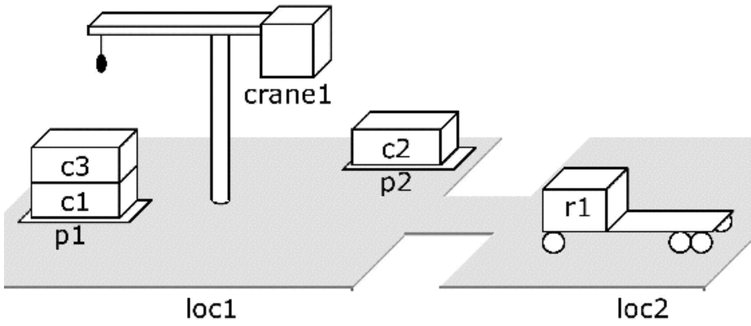
;; crane k at location l takes c off of d in pile p

precond: belong(k, l), attached(p, l), empty(k), top(c, p), on(c, d)

effects: holding(k, c), $\neg$ empty(k), $\neg$ in(c, p), $\neg$ top(c, p), $\neg$ on(c, d), top(d, p)

Actions

- **Action:** ground instance (via substitution) of an operator



take(k, l, c, d, p)
;; crane k at location l takes c off of d in pile p
precond: belong(k, l), attached(p, l), empty(k), top(c, p), on(c, d)
effects: holding(k, c), $\neg$ empty(k), $\neg$ in(c, p), $\neg$ top(c, p), $\neg$ on(c, d), top(d, p)

take(crane1,loc1,c3,c1,p1)
;; crane crane1 at location loc1 takes c3 off c1 in pile p1
precond: belong(crane1,loc1), attached(p1,loc1), empty(crane1), top(c3,p1), on(c3,c1)
effects: holding(crane1,c3), ¬empty(crane1), ¬in(c3,p1), ¬top(c3,p1), ¬on(c3,c1), top(c1,p1)

Notation

- Let *a* be an operator or action. Then
  - $\text{precond}^+(a)$ = {atoms that appear positively in *a*'s preconditions}
  - $\text{precond}^-(a)$ = {atoms that appear negatively in *a*'s preconditions}
  - $\text{effects}^+(a)$ = {atoms that appear positively in *a*'s effects}
  - $\text{effects}^-(a)$ = {atoms that appear negatively in *a*'s effects}

E.g.,

$\text{take}(k, l, c, d, p)$

;; crane k at location l takes c off of d in pile p

precond: $\text{belong}(k, l), \text{attached}(p, l), \text{empty}(k), \text{top}(c, p), \text{on}(c, d)$

effects: $\text{holding}(k, c), \neg\,\text{empty}(k), \neg\,\text{in}(c, p), \neg\,\text{top}(c, p), \neg\,\text{on}(c, d), \text{top}(d, p)$

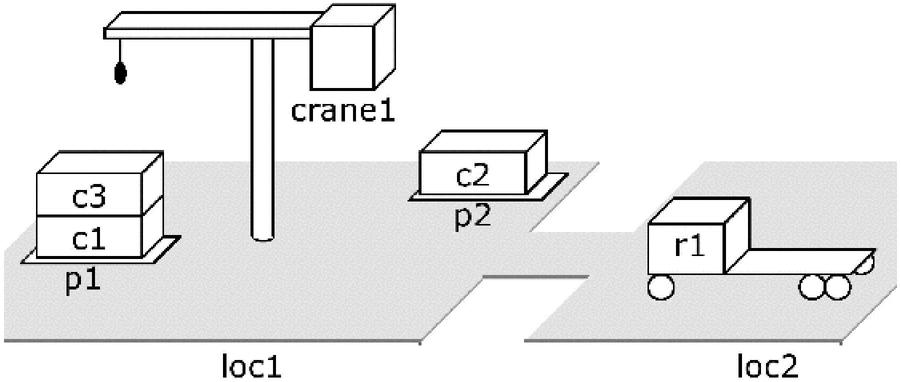
- $\text{effects}^+(\text{take}(k,l,c,d,p)$ = {holding(k,c), top(d,p)}
- $\text{effects}^-(\text{take}(k,l,c,d,p)$ = {empty(k), in(c,p), top(c,p), on(c,d)}

Aside: Some things to note

- The state only explicitly represents what is **true**. The semantics of this representation is that any fluent not included in the state is **false** – just like a database. *(Recall that one of the assumptions of classical planning is complete initial (and subsequent) state. The problem would be a lot harder w/o this assumption!!)*
- **Terminology:** an action is a ground operator. In the Knowledge Representation (KR) literature the concept of an “operator” is not used. Actions may be ground or unground.
- Classical planners generally operate over ground actions.

Applicability

- An action *a* is ***applicable*** to a state *s* if *s* satisfies precond(*a*),
  - i.e., if precond$^+$(a) $\subseteq s$ and precond$^-$(a) $\cap\, s = \varnothing$
- Here are an action and a state that it's applicable to:



take(crane1,loc1,c3,c1,p1)

;; crane crane1 at location loc1 takes c3 off c1 in pile p1

precond: belong(crane1,loc1), attached(p1,loc1),
empty(crane1), top(c3,p1), on(c3,c1)

effects: holding(crane1,c3), ¬empty(crane1), ¬in(c3,p1),
¬top(c3,p1), ¬on(c3,c1), top(c1,p1)

Result of Performing an Action

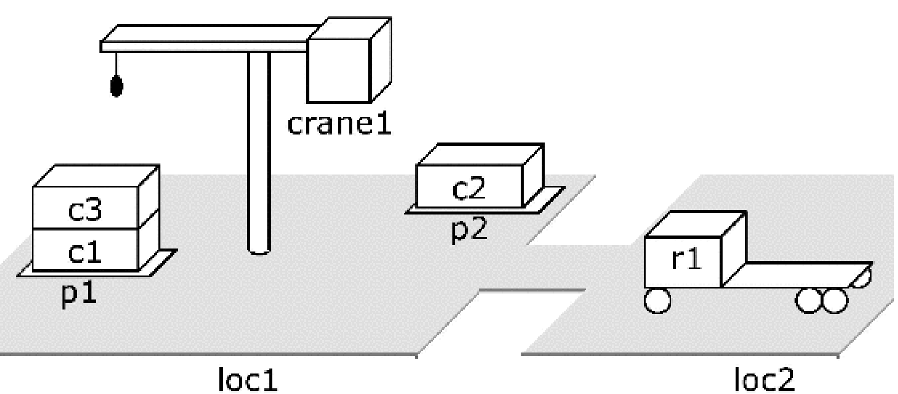
- If a is applicable to s, the **result of performing** it is

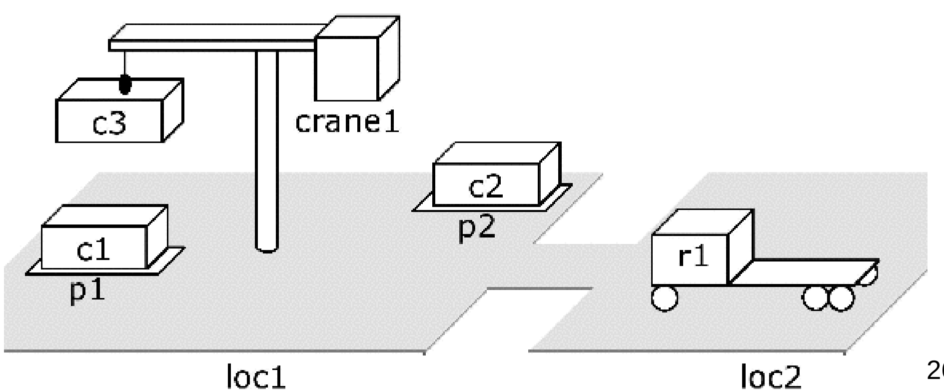
$$\gamma(s,a) = (s - \text{effects}^{-}(a)) \cup \text{effects}^{+}(a)$$

Set of things that are true. (if not in set then false)

  - Delete negative effects, and add positive ones

take(crane1,loc1,c3,c1,p1)
;; crane crane1 at location loc1 takes c3 off c1 in pile p1
precond: belong(crane1,loc1), attached(p1,loc1), empty(crane1), top(c3,p1), on(c3,c1)
effects: holding(crane1,c3), ¬empty(crane1), ¬in(c3,p1), ¬top(c3,p1), ¬on(c3,c1), top(c1,p1)





Operators for the DWR Domain

move(r, l, m)
;; robot r moves from location l to location m
precond: adjacent(l, m), at(r, l), $\neg$ occupied(m)
effects: at(r, m), occupied(m), $\neg$ occupied(l), $\neg$ at(r, l)

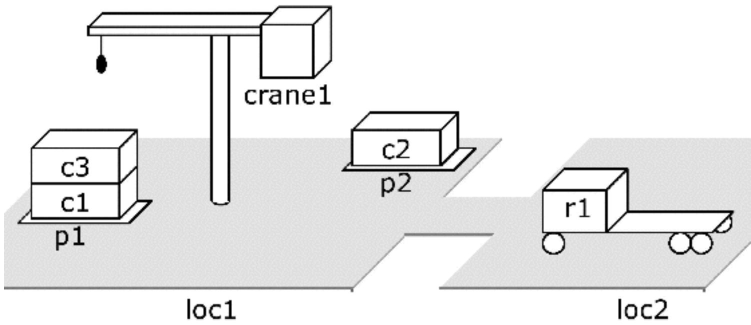
load(k, l, c, r)
;; crane k at location l loads container c onto robot r
precond: belong(k, l), holding(k, c), at(r, l), unloaded(r)
effects: empty(k), $\neg$ holding(k, c), loaded(r, c), $\neg$ unloaded(r)

unload(k, l, c, r)
;; crane k at location l takes container c from robot r
precond: belong(k, l), at(r, l), loaded(r, c), empty(k)
effects: $\neg$ empty(k), holding(k, c), unloaded(r), $\neg$ loaded

put(k, l, c, d, p)
;; crane k at location l puts c onto d in pile p
precond: belong(k, l), attached(p, l), holding(k, c), top(d, p)
effects: $\neg$ holding(k, c), empty(k), in(c, p), top(c, p), on(c, d), $\neg$ top(d, p)

take(k, l, c, d, p)
;; crane k at location l takes c off of d in pile p
precond: belong(k, l), attached(p, l), empty(k), top(c, p), on(c, d)
effects: holding(k, c), $\neg$ empty(k), $\neg$ in(c, p), $\neg$ top(c, p), $\neg$ on(c, d), top(d, p)

- Planning domain:
  language & operators
- Operators corresponds to a set of state-transition systems



Planning Problems

Given a planning domain (language *L*, operators *O*)

- ***Encoding*** of a planning problem: a triple $P=(O,s_0,g)$
  - *O* is the collection of operators
  - s_0 is a state (the initial state)
  - *g* is a set of literals (the goal formula)
- The ***actual planning problem***: $\mathcal{P} = (\Sigma, s_0, g)$
  - s_0 and *g* are as above
  - $\Sigma = (S,A,\gamma)$ is a state-transition system
  - *S* = {all sets of ground atoms in *L*}
  - *A* = {all ground instances of operators in *O*}
  - γ = state-transition function determined by the operators

Plans and Solutions

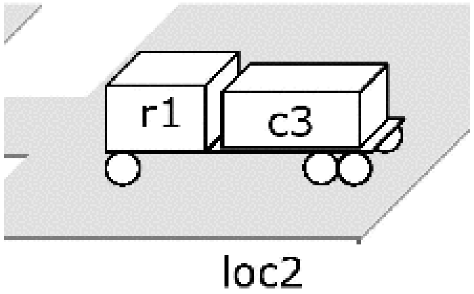
- **Plan*:** any sequence of actions $\sigma = \langle a_1, a_2, \ldots, a_n \rangle$ such that each a_i is a ground instance of an operator in O
- The plan is a ***solution*** for $P=(O,s_0,g)$ if it is executable and achieves g
  - i.e., if there are states $s_0, s_1, \ldots, s_n$ such that
    - $\gamma(s_0,a_1) = s_1$
    - $\gamma(s_1,a_2) = s_2$
    - …
    - $\gamma(s_{n-1},a_n) = s_n$
    - s_n satisfies g

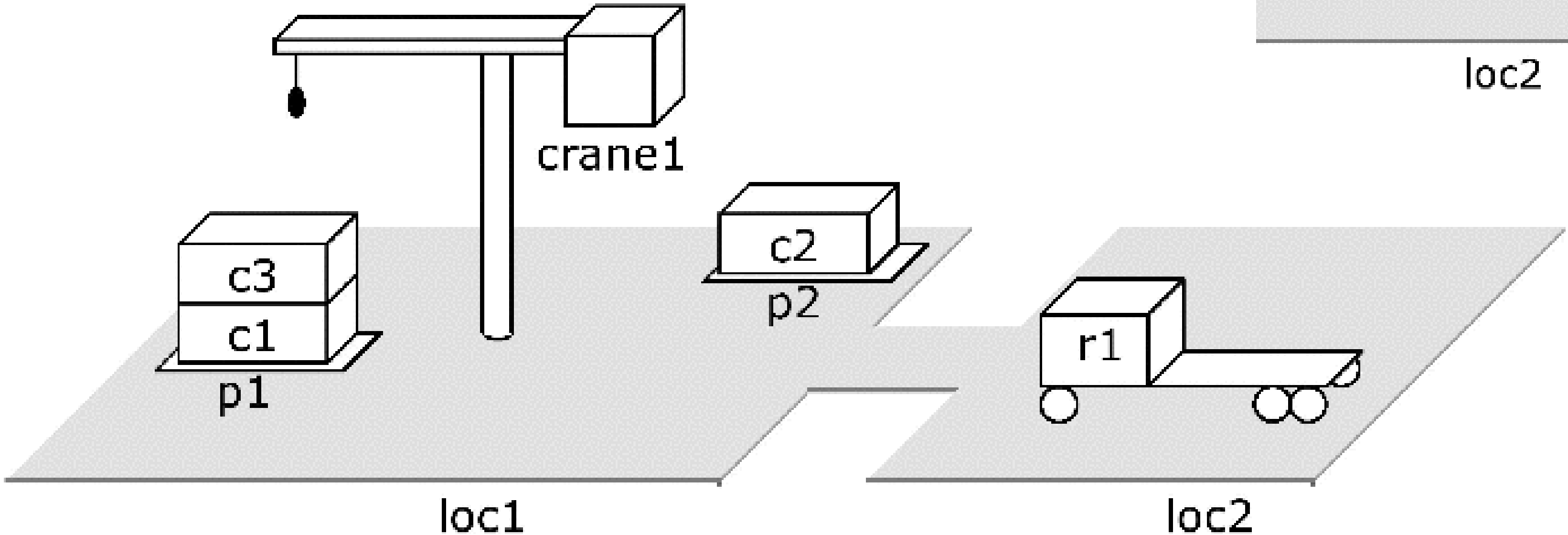
** Recall that we are restricting our attention to “Classical Planning”*

Example

- Let $P_1 = (O, s_1, g_1)$, where
  - O is the set of operators given earlier

g_1 = {loaded(r1,c3), at(r1,loc2)}



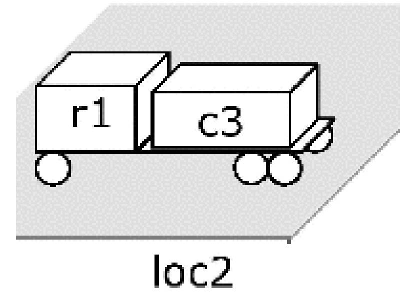


s_1={attached(p1,loc1), in(c1,p1), in(c3,p1), top(c3,p1), on(c3,c1), on(c1,pallet), attached(p2,loc1), in(c2,p2), top(c2,p2), on(c2,pallet), belong(crane1,loc1), empty(crane1), adjacent(loc1,loc2), adjacent(loc2,loc1), at(r1,loc2), occupied(loc2), unloaded(r1)}.

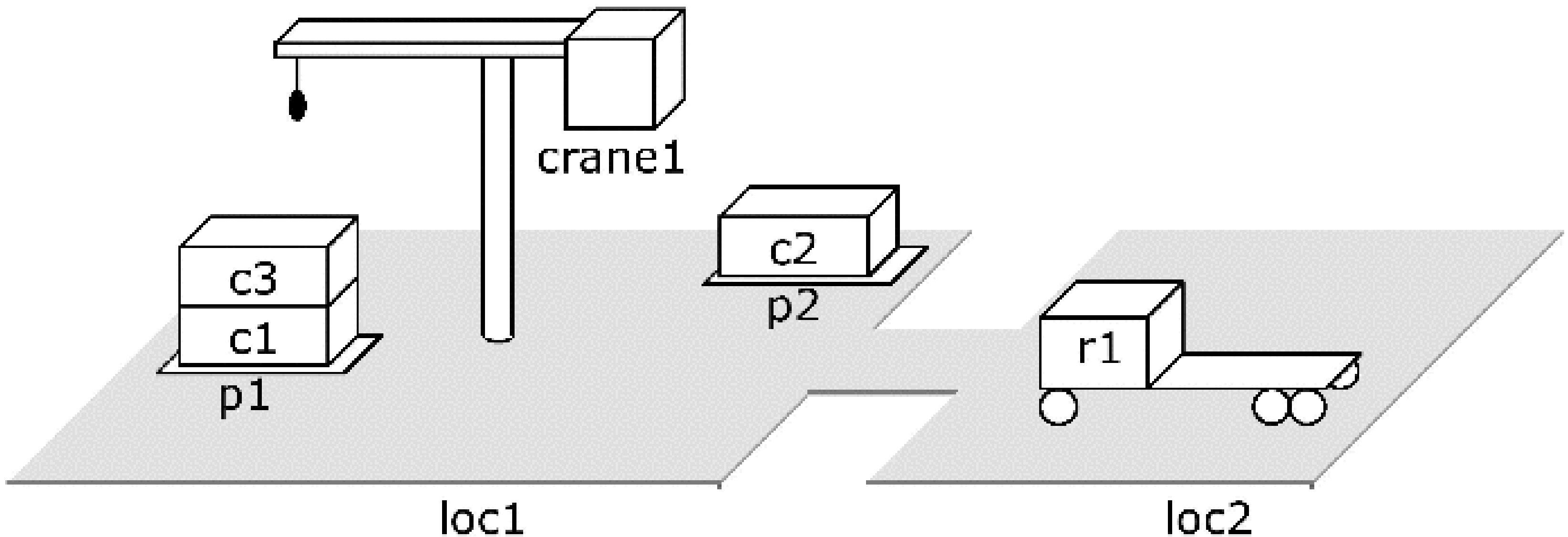
Example

GOAL STATE:

$g_1 = \{$loaded(r1,c3),at(r1,loc2)$\}$

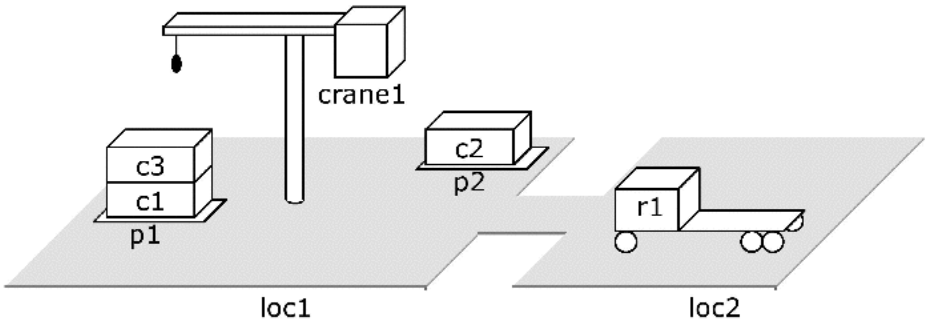


INITIAL STATE:

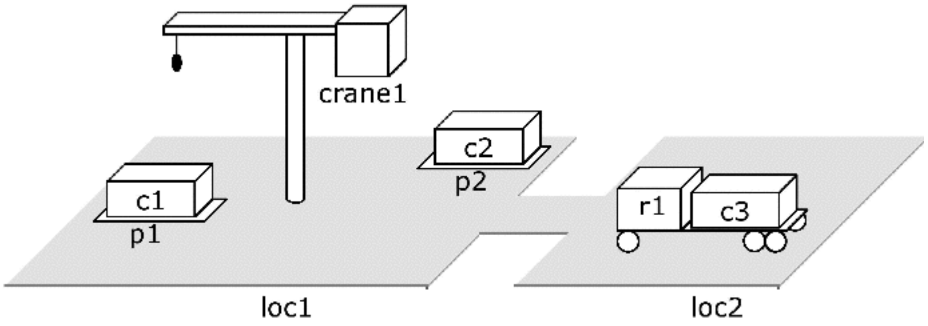


The DWR state $s_1 = \{$attached(p1,loc1), in(c1,p1), in(c3,p1), top(c3,p1), on(c3,c1), on(c1,pallet), attached(p2,loc1), in(c2,p2), top(c2,p2), on(c2,pallet), belong(crane1,loc1), empty(crane1), adjacent(loc1,loc2), adjacent(loc2,loc1), at(r1,loc2), occupied(loc2), unloaded(r1)$\}$.

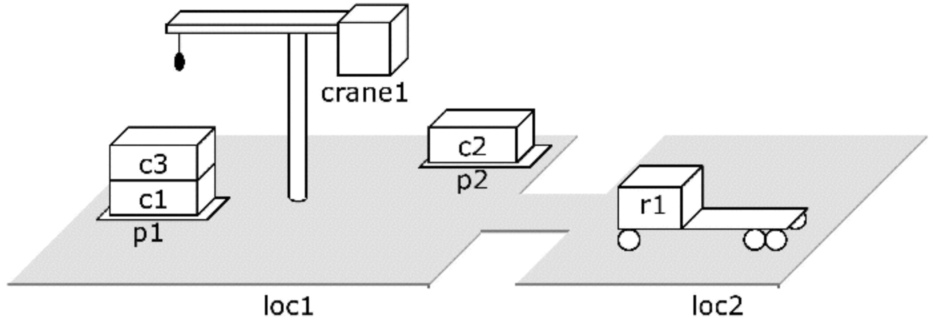
Example (cont.)



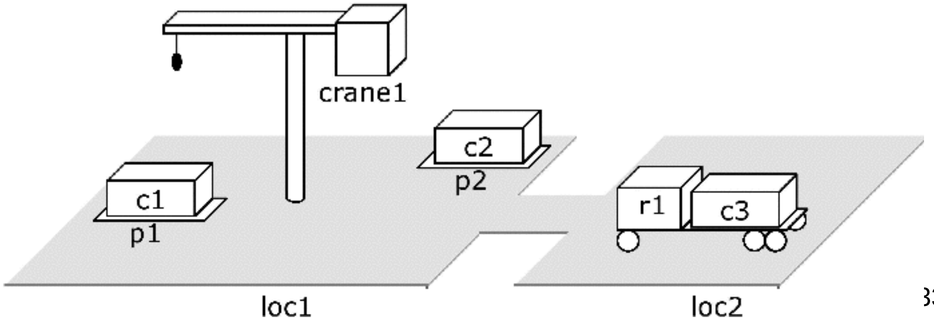
- Here are three solutions for P_1:
  - ⟨take(crane1,loc1,c3,c1,p1), move(r1,loc2,loc1), move(r1,loc1,loc2), move(r1,loc2,loc1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
  - ⟨take(crane1,loc1,c3,c1,p1), move(r1,loc2,loc1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
  - ⟨move(r1,loc2,loc1), take(crane1,loc1,c3,c1,p1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
- Each produces:



Example (cont.)

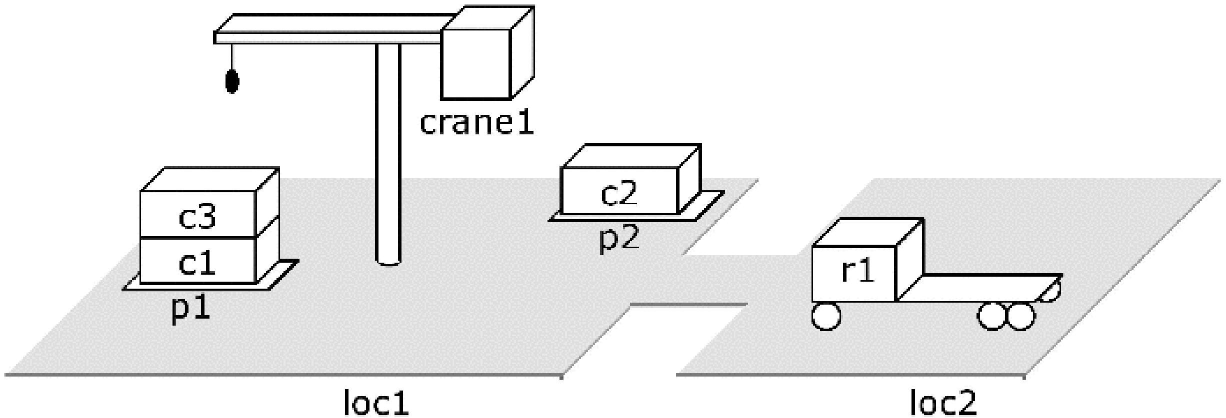


- First is *redundant*: can remove actions and still have a solution
  1. ⟨take(crane1,loc1,c3,c1,p1), move(r1,loc2,loc1), move(r1,loc1,loc2), move(r1,loc2,loc1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
  2. ⟨take(crane1,loc1,c3,c1,p1), move(r1,loc2,loc1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
  3. ⟨move(r1,loc2,loc1), take(crane1,loc1,c3,c1,p1), load(crane1,loc1,c3,r1), move(r1,loc1,loc2)⟩
- 2nd and 3rd are *irredundant and shortest*



2. Set-Theoretic Representation

Like classical rep'n, but restricted to **propositional logic.**



- States:
  - Instead of a collection of ground atoms …

    {on(c1,pallet), on(c1,r1), on(c1,c2), …, at(r1,l1), at(r1,l2), …}

  … use a collection of propositions (boolean variables):

    {on-c1-pallet, on-c1-r1, on-c1-c2, …, at-r1-l1, at-r1-l2, …}

Instead of operators like this one,

take(k, l, c, d, p)
;; crane k at location l takes c off of d in pile p
precond: belong(k, l), attached(p, l), empty(k), top(c, p), on(c, d)
effects: holding(k, c), $\neg$ empty(k), $\neg$ in(c, p), $\neg$ top(c, p), $\neg$ on(c, d), top(d, p)

Take all of the operator **instances**, E.g.:

take(crane1,loc1,c3,c1,p1)
;; crane crane1 at location loc1 takes c3 off c1 in pile p1
precond: belong(crane1,loc1), attached(p1,loc1),
empty(crane1), top(c3,p1), on(c3,c1)
effects: holding(crane1,c3), ¬empty(crane1), ¬in(c3,p1),
¬top(c3,p1), ¬on(c3,c1), top(c1,p1)

And rewrite ground atoms as **propositions**, E.g.:

take-crane1-loc1-c3-c1-p1
precond: belong-crane1-loc1, attached-p1-loc1,empty-crane1, top-c3-p1, on-c3-c1
delete: empty-crane1, in-c3-p1, top-c3-p1, on-c3-p1
add: holding-crane1-c3, top-c1-p1

Comparison

A set-theoretic representation is equivalent to a classical representation in which all of the atoms are ground

Problem: Exponential blowup

- If a classical operator contains n atoms and each atom has arity k, then it corresponds to c^{nk} actions where c = |{constant symbols}|

3. State-Variable Representation (aka FDR)

- Non-fluents (properties that don't change) are ground relations:

  e.g., adjacent(loc1,loc2)

- Fluents are functions:

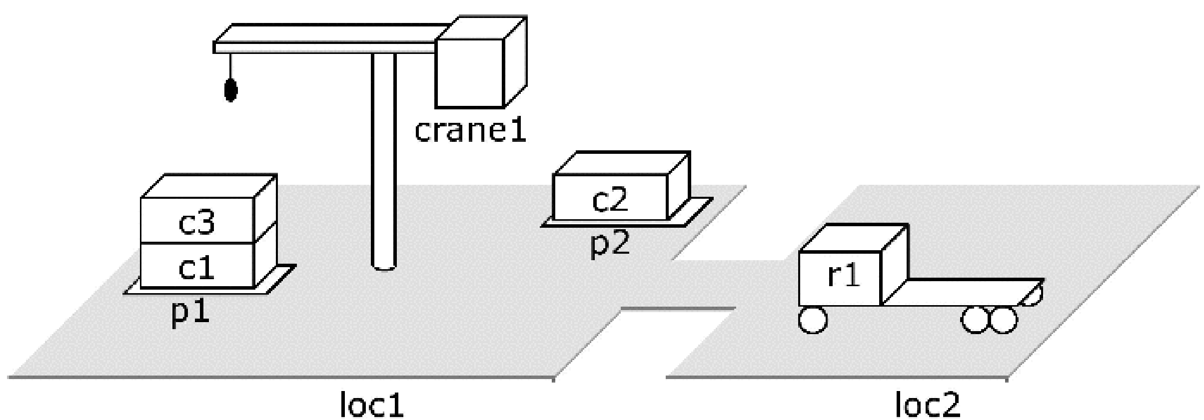
  i.e., for properties that can change, assign values to *state variables*

- Classical and state-variable rep'ns take similar amounts of space

  each can be translated into the other in low-order polynomial time

move(r, l, m)
  ;; robot r at location l moves to an adjacent location m
  precond: rloc(r) $=$ l, adjacent(l, m)
  effects: rloc(r) $\leftarrow$ m

{top(p1)=c3,
cpos(c3)=c1,
cpos(c1)=pallet,
holding(crane1)=nil,
rloc(r1)=loc2,
loaded(r1)=nil, …}



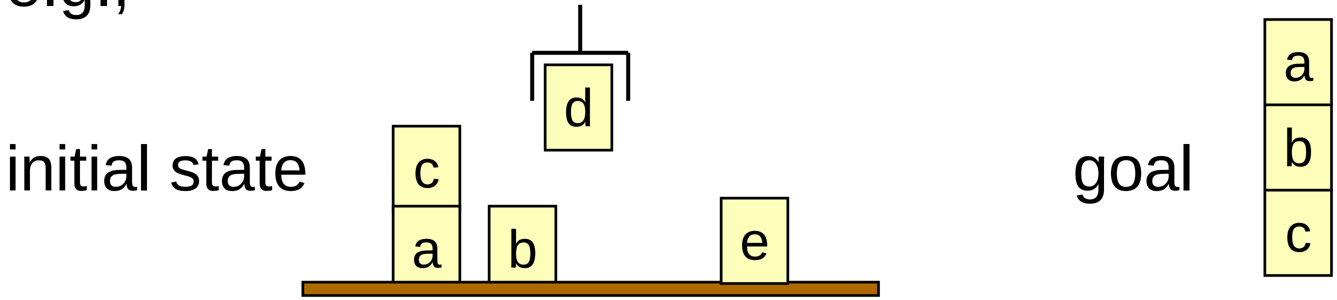
State-Variable Representation (cont.)

- Captures further information about the state. E.g., that state variables can only take on one of the values in the domain. This helps reduce the search space.
- Basis for the SAS and SAS+ formalisms (used most recently in the FastDownward Planner (FD) and its descendents (e.g., LAMA, etc)
- Basis for encodings further plan properties such as domain transition graphs (DTGs) and causal graphs (CG)

Example: The Blocks World
(Review on your own)

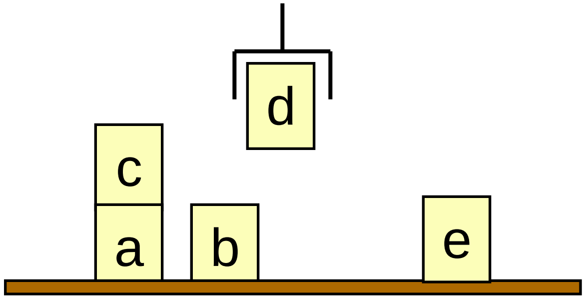
Example: The Blocks World

- Infinitely wide table, finite number of children's blocks
- Ignore where a block is located on the table
- A block can sit on the table or on another block
- Want to move blocks from one configuration to another
  - e.g.,



- Classical, set-theoretic, and state-variable formulations for the case of FIVE BLOCKS follow.

1. Example Classical Representation



- Constant symbols:
  - The blocks: a, b, c, d, e
- Predicates:
  - ontable(*x*) - block *x* is on the table
  - on(*x*,*y*) - block *x* is on block *y*
  - clear(*x*) - block *x* has nothing on it
  - holding(*x*) - the robot hand is holding block *x*
  - handempty - the robot hand isn't holding anything

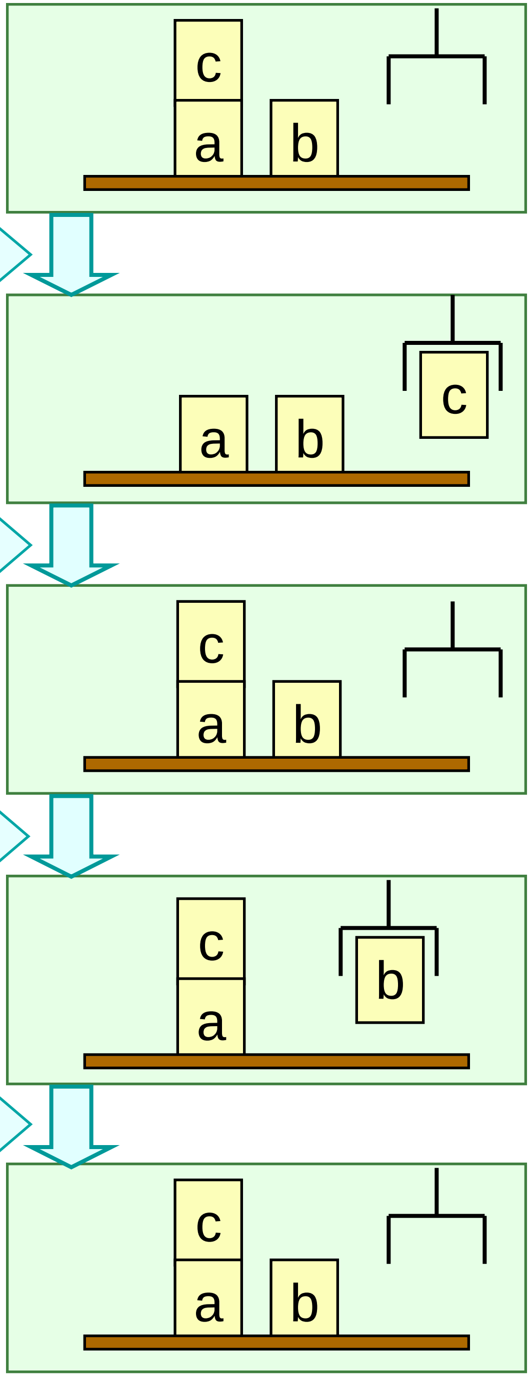
Classical Operators

unstack(*x*,*y*)
Precond: on(*x*,*y*), clear(*x*), handempty
Effects: ~on(*x*,*y*), ~clear(*x*), ~handempty, holding(*x*), clear(*y*)

stack(*x*,*y*)
Precond: holding(*x*), clear(*y*)
Effects: ~holding(*x*), ~clear(*y*), on(*x*,*y*), clear(*x*), handempty

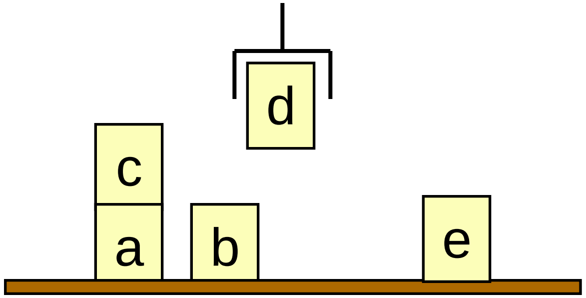
pickup(*x*)
Precond: ontable(*x*), clear(*x*), handempty
Effects: ~ontable(*x*), ~clear(*x*), ~handempty, holding(*x*)

putdown(*x*)
Precond: holding(*x*)
Effects: ~holding(*x*), ontable(*x*), clear(*x*), handempty



2. Example Set-Theoretic Representation

For five blocks, **36 propositions, 50 actions**



E.g.,

ontable-a	- block a is on the table
on-c-a	- block c is on block a
clear-c	- block c has nothing on it
holding-d	- the robot hand is holding block d
handempty	- the robot hand isn't holding anything
… (31 more)	

Set-Theoretic Actions

E.g.,

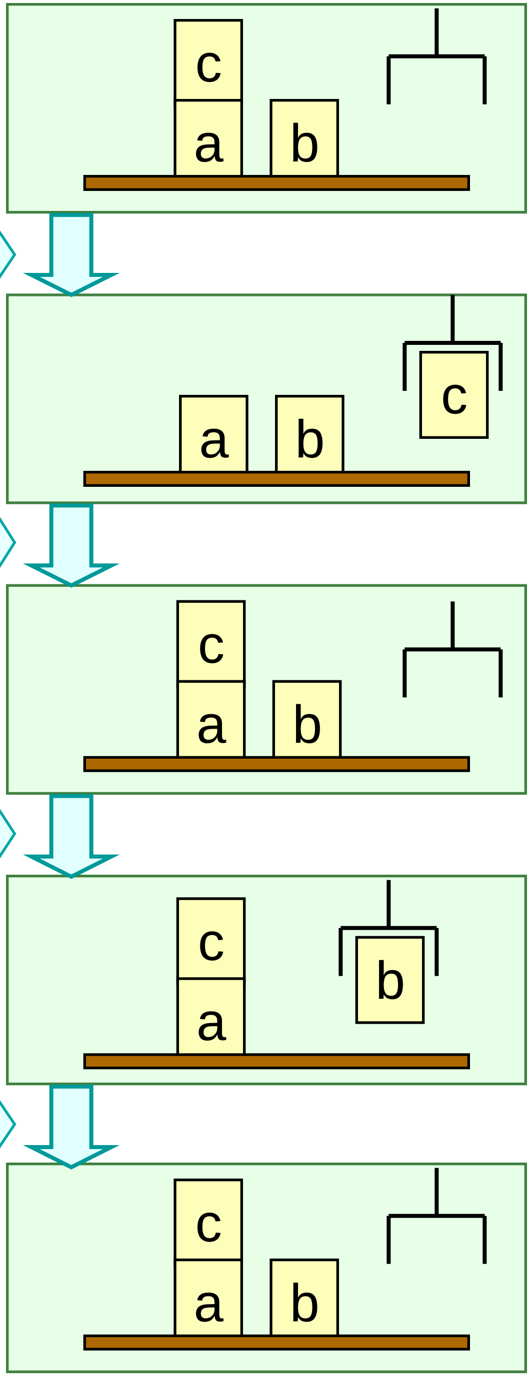
unstack-c-a
Pre: on-c,a, clear-c, handempty
Del: on-c,a, clear-c, handempty
Add: holding-c, clear-a

stack-c-a
Pre: holding-c, clear-a
Del: holding-c, clear-a
Add: on-c-a, clear-c, handempty

pickup-c
Pre: ontable-c, clear-c, handempty
Del: ontable-c, clear-c, handempty
Add: holding-c

putdown-c
Pre: holding-c
Del: holding-c
Add: ontable-c, clear-c, handempty

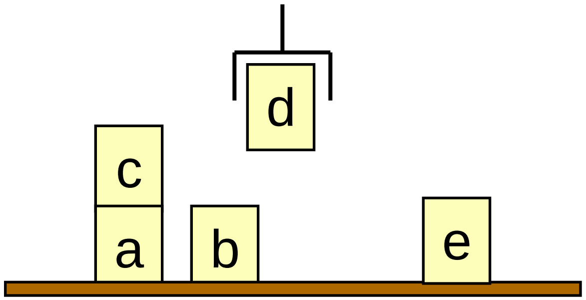
. . . (46 more)



3. Example State-Variable Representation

- Constant symbols:

a, b, c, d, e	of type block
0, 1, table, nil	of type other



- State variables:

pos(*x*) = y	if block *x* is on block *y*
pos(*x*) = table	if block *x* is on the table
pos(*x*) = nil	if block *x* is being held
clear(*x*) = 1	if block *x* has nothing on it
clear(*x*) = 0	if block *x* is being held or has a block on it
holding = *x*	if the robot hand is holding block *x*
holding = nil	if the robot hand is holding nothing

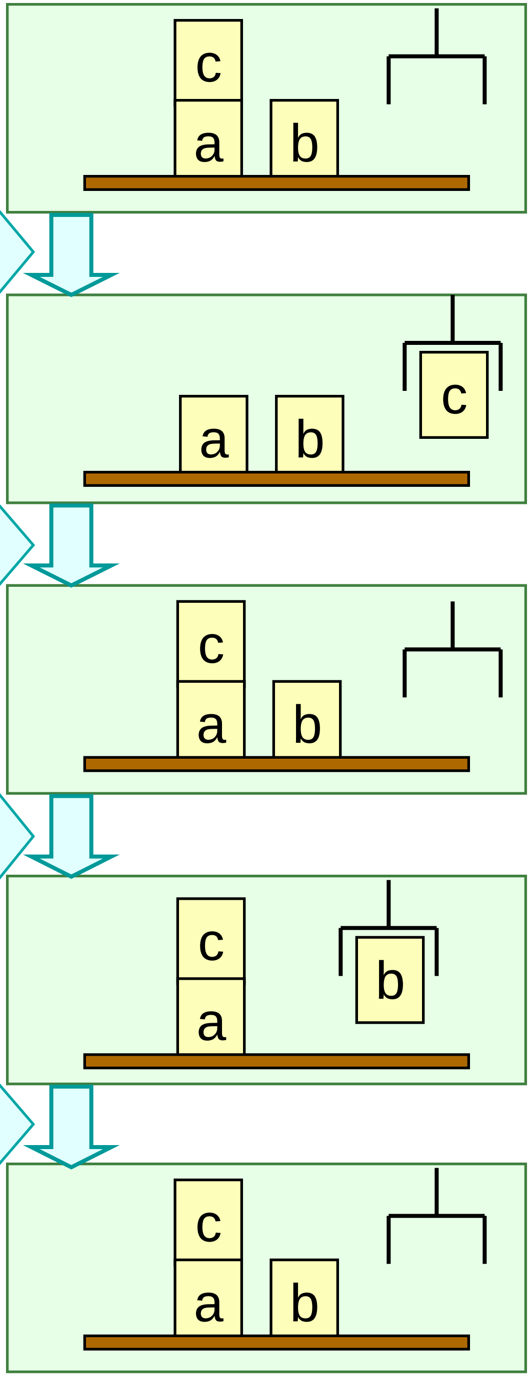
State-Variable Operators

unstack(*x* : block, *y* : block)
Precond: pos(*x*)=*y*, clear(*y*)=0, clear(*x*)=1, holding=nil
Effects: pos(*x*)=nil, clear(*x*)=0, holding=*x*, clear(*y*)=1

stack(*x* : block, *y* : block)
Precond: holding=*x*, clear(*x*)=0, clear(*y*)=1
Effects: holding=nil, clear(*y*)=0, pos(*x*)=y, clear(*x*)=1

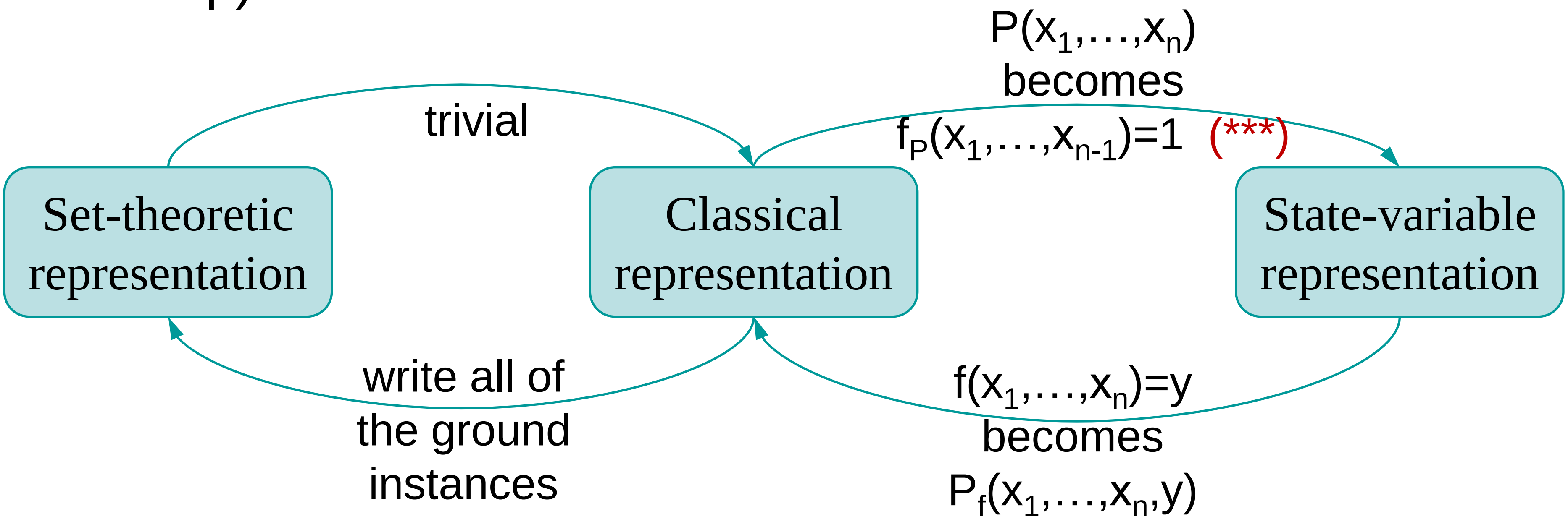
pickup(*x* : block)
Precond: pos(*x*)=table, clear(*x*)=1, holding=nil
Effects: pos(*x*)=nil, clear(*x*)=0, holding=*x*

putdown(*x* : block)
Precond: holding=*x*
Effects: holding=nil, pos(*x*)=table, clear(*x*)=1



Representational Equivalence

- Any problem that can be represented in one representation can also be represented in the other two
- Can convert in linear time and space, except when converting to set-theoretic (where we get an exponential blowup)



(***) trivially, or there can be a more parsimonious problem-specific encoding that ignores irrelevant variables

Comparison

- Classical representation
  - Most popular for classical planning, basis of PDDL
- Set-theoretic representation
  - Can take much more space than classical representation
  - Useful in algorithms that manipulate ground atoms directly
    - e.g., planning graphs, SAT
  - Useful for certain kinds of theoretical studies
- State-variable representation (e.g., SAS, SAS+,"FDR")
  - Equivalent to classical representation in expressive power
  - Arguably less natural to conceive
  - Clever problem-specific encodings can be much more compact and embed critical info (e.g., one-of constraints)
  - Leveraged in many of the state-of-the-art heuristic search classical planners (e.g., FD, LAMA, etc)
  - Useful in non-classical planning problems as a way to handle numbers, functions, time

Extending Expressivity: ADL*

- Previous representations were so-called "STRIPS" rep'ns. These have useful properties for automatically generating classical plans, but are not always sufficient to express the behaviour of more complex domains.
- ADL is a richer, and thus more compact, representation language that allows for
  - Disjunction and Quantification in *preconditions* and *goals*
  - *Effects* that are Quantified, and/or Conditional (effect is conditioned on state)
- PDDL supports STRIPS and ADL, but not all planners support ADL, and not all planners even support a so-called Classical Representation
- In the KR community ADL or greater is common.

* ADL = "Action Description Language", [Pednault, KR89]

Pros/Cons: Compiling to Canonical Action Rep'n

Possible to compile down ADL actions into STRIPS actions

- Quantification -> conjunctions/disjunctions over finite universes
- Actions with conditional effects -> multiple (exponentially more) actions without conditional effects
- Actions with disjunctive effects -> multiple actions, each of which take one of the disjuncts as their preconditions (*called "determinization")*
- Domain axioms (ramifications) -> the individual effects of the actions; so all actions satisfy STRIPS assumption

Compilation is not always a win-win.

- By compiling down to canonical form, we can concentrate on highly efficient planning for canonical actions
  - However, often compilation leads to an exponential blowup and makes it harder to exploit the structure of the domain
- By leaving actions in non-canonical form, we can often do more compact encoding of the domains as well as more efficient search
  - However, we will have to continually extend planning algorithms to handle these representations