

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:

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Quick Review of Classical Planning

8 restrictive assumptions req'd:

A0: Finite

A1: Fully observable

A2: Deterministic

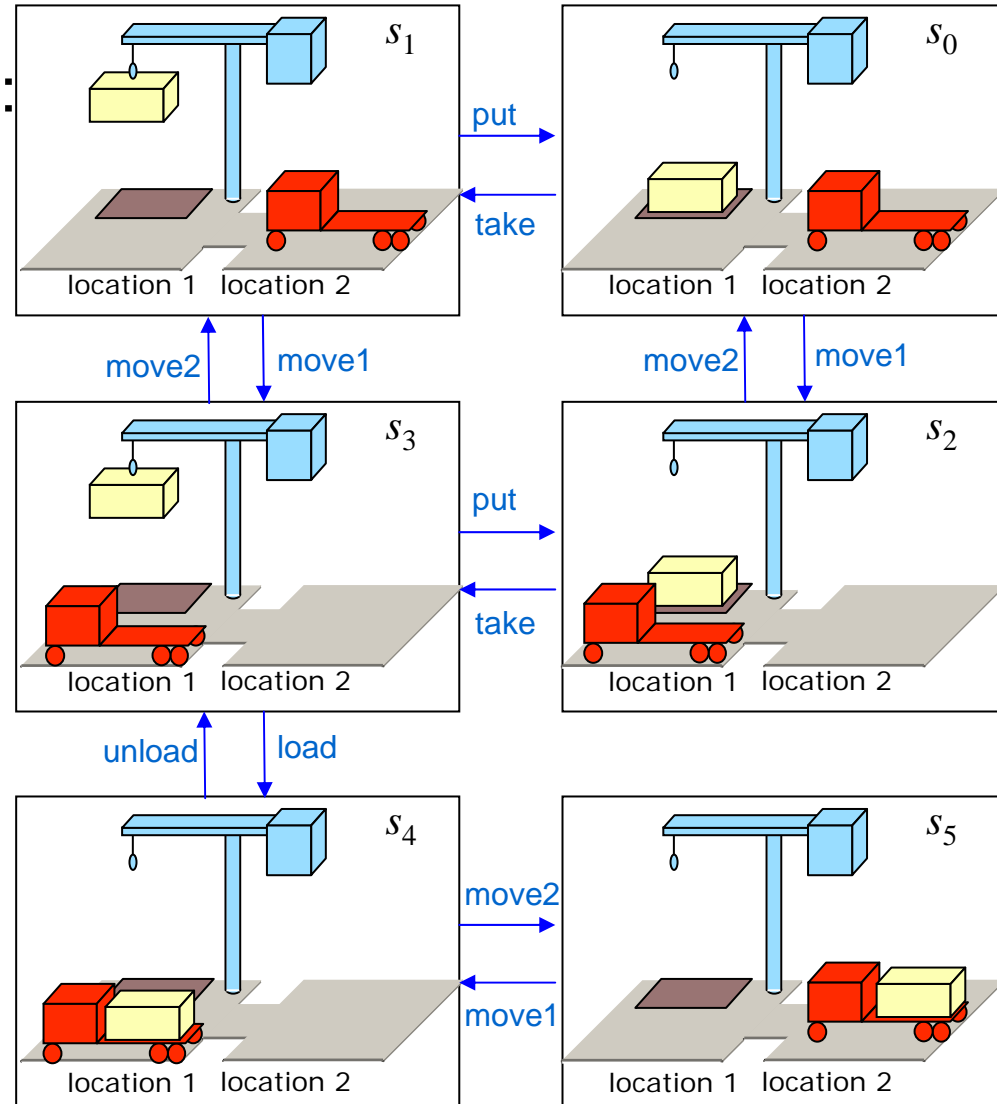
A3: Static

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?

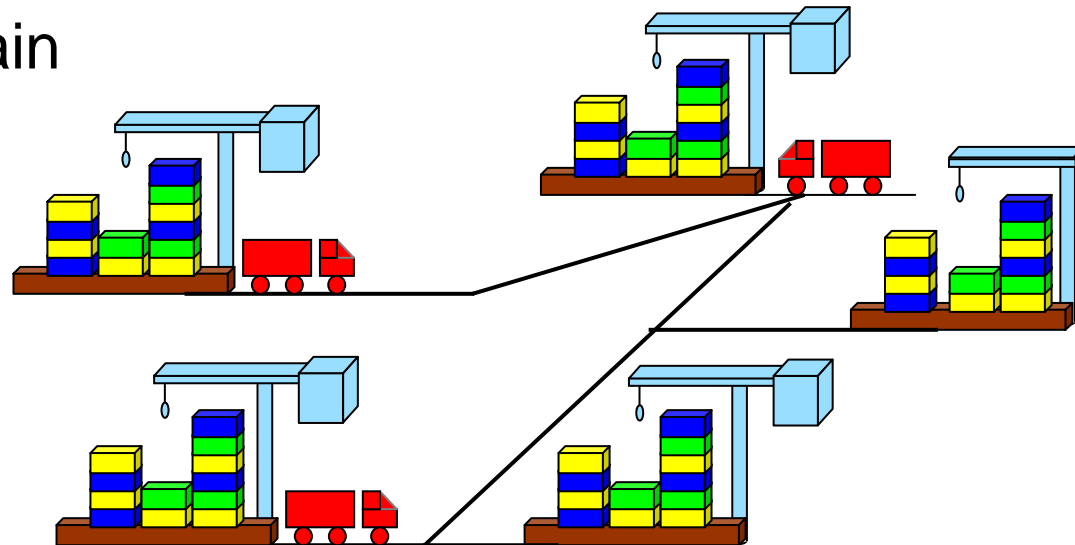
- In an explicit transition system, actions are represented as state-to-state transitions. Each action will be represented by an incidence matrix of size $|S| \times |S|$
- In the proposed model, actions are represented only in terms of state variables whose values they care about, and whose value they 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 v_1 to be true and makes v_7 to be false, it can be represented by just 2 bits (instead of a 1024×1024 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
 - The assumption being made here is that the actions will have effects on a small number of state variables.

Outline

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

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: l_1, l_2, \dots
 - Containers: c_1, c_2, \dots
 - Piles: p_1, p_2, \dots
 - Robot carts: r_1, r_2, \dots
 - Cranes: k_1, k_2, \dots

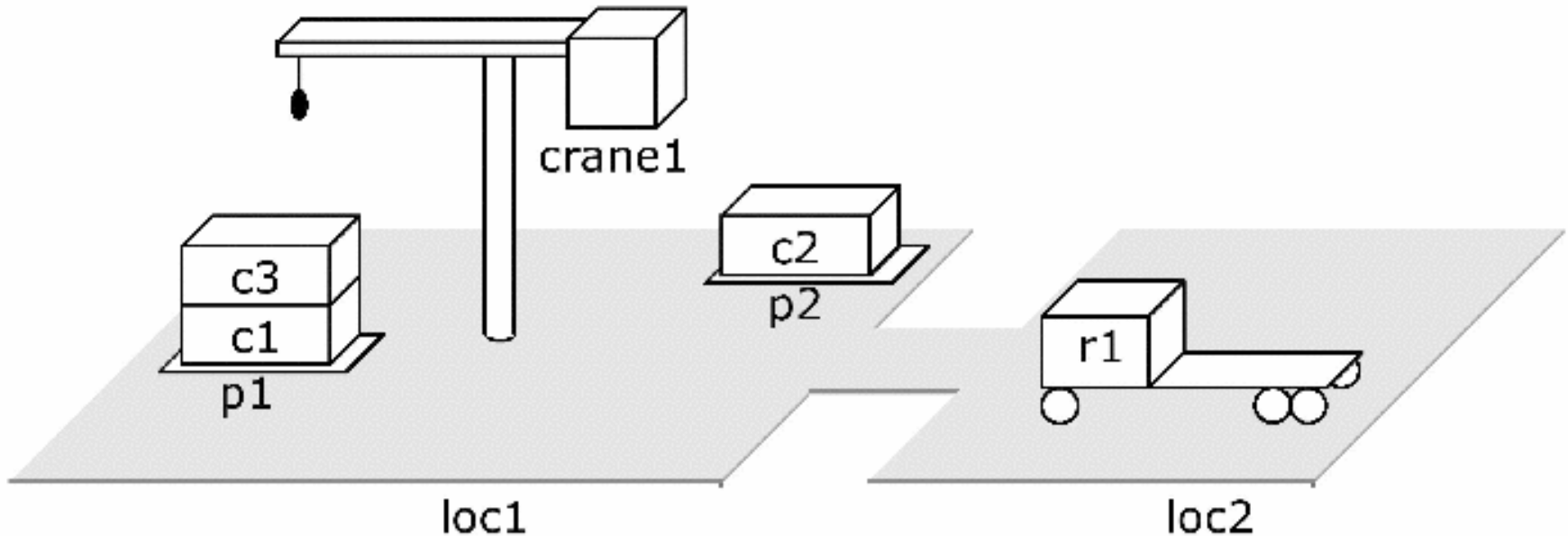


Classical Representation

- *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*: $\theta = \{x_1 \leftarrow v_1, x_2 \leftarrow v_2, \dots, x_n \leftarrow v_n\}$
 - Each x_i is a variable symbol; each v_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 $o=(\text{name}(o), \text{precond}(o), \text{effects}(o))$
 - $\text{name}(o)$ is a syntactic expression of the form $n(x_1, \dots, x_k)$
 - n : *operator symbol* - must be unique for each operator
 - x_1, \dots, x_k : variable symbols (parameters)
 - must include every variable symbol in o
 - $\text{precond}(o)$: *preconditions*
 - literals that must be true in order to use the operator
 - $\text{effects}(o)$: *effects*
 - literals the operator will make true

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

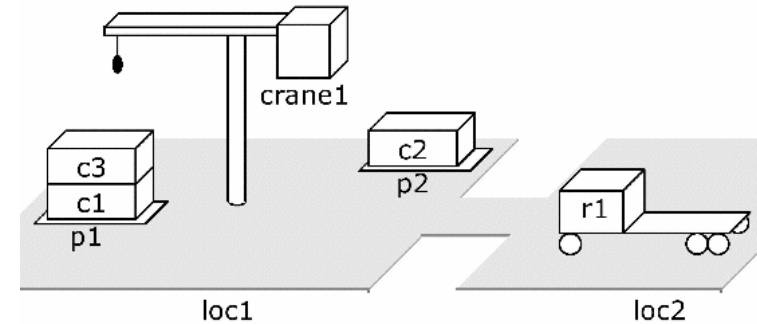
;; crane k at location l takes c off of d in pile p

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

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

Actions

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



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

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

$\text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1})$

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

precond: $\text{belong}(\text{crane1}, \text{loc1}), \text{attached}(\text{p1}, \text{loc1}),$
 $\text{empty}(\text{crane1}), \text{top}(\text{c3}, \text{p1}), \text{on}(\text{c3}, \text{c1})$

effects: $\text{holding}(\text{crane1}, \text{c3}), \neg \text{empty}(\text{crane1}), \neg \text{in}(\text{c3}, \text{p1}),$
 $\neg \text{top}(\text{c3}, \text{p1}), \neg \text{on}(\text{c3}, \text{c1}), \text{top}(\text{c1}, \text{p1})$

Notation

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

E.g.,

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

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

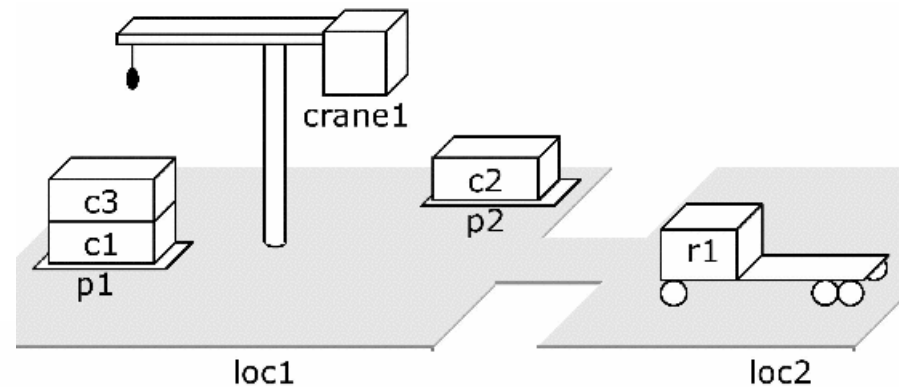
precond: $\text{belong}(k, l), \text{attached}(p, l), \text{empty}(k), \text{top}(c, p), \text{on}(c, d)$

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

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

Applicability

- An action a is *applicable* to a state s if s satisfies $\text{precond}(a)$,
 - i.e., if $\text{precond}^+(a) \subseteq s$ and $\text{precond}^-(a) \cap s = \emptyset$
- 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), \neg empty(crane1), \neg in(c3,p1),
 \neg top(c3,p1), \neg on(c3,c1), top(c1,p1)`

Result of Performing an Action

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

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

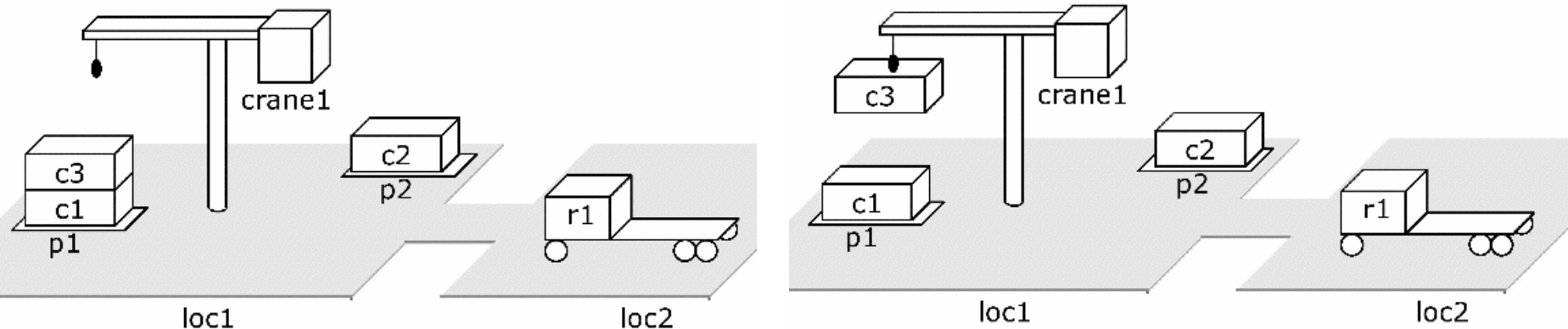
- Delete negative effects, and add positive ones

`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), \neg empty(crane1), \neg in(c3,p1),
 \neg top(c3,p1), \neg on(c3,c1), top(c1,p1)`



Operators for the DWR Domain

$\text{move}(r, l, m)$

:: robot r moves from location l to location m

precond: $\text{adjacent}(l, m), \text{at}(r, l), \neg \text{occupied}(m)$

effects: $\text{at}(r, m), \text{occupied}(m), \neg \text{occupied}(l), \neg \text{at}(r, l)$

$\text{load}(k, l, c, r)$

:: crane k at location l loads container c onto robot r

precond: $\text{belong}(k, l), \text{holding}(k, c), \text{at}(r, l), \text{unloaded}(r)$

effects: $\text{empty}(k), \neg \text{holding}(k, c), \text{loaded}(r, c), \neg \text{unloaded}(r)$

$\text{unload}(k, l, c, r)$

:: crane k at location l takes container c from robot r

precond: $\text{belong}(k, l), \text{at}(r, l), \text{loaded}(r, c), \text{empty}(k)$

effects: $\neg \text{empty}(k), \text{holding}(k, c), \text{unloaded}(r), \neg \text{loaded}$

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

:: crane k at location l puts c onto d in pile p

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

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

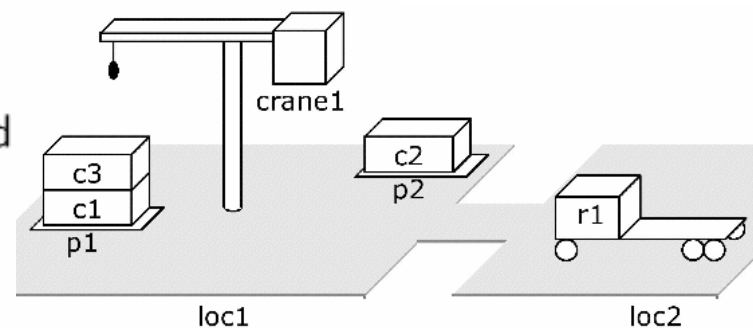
$\text{take}(k, l, c, d, p)$

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

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



Planning Problems

Given a planning domain (language L , operators O)

- *Statement* 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
 - $S = \{\text{all sets of ground atoms in } L\}$
 - $A = \{\text{all ground instances of operators in } O\}$
 - $\gamma = \text{state-transition function determined by the operators}$

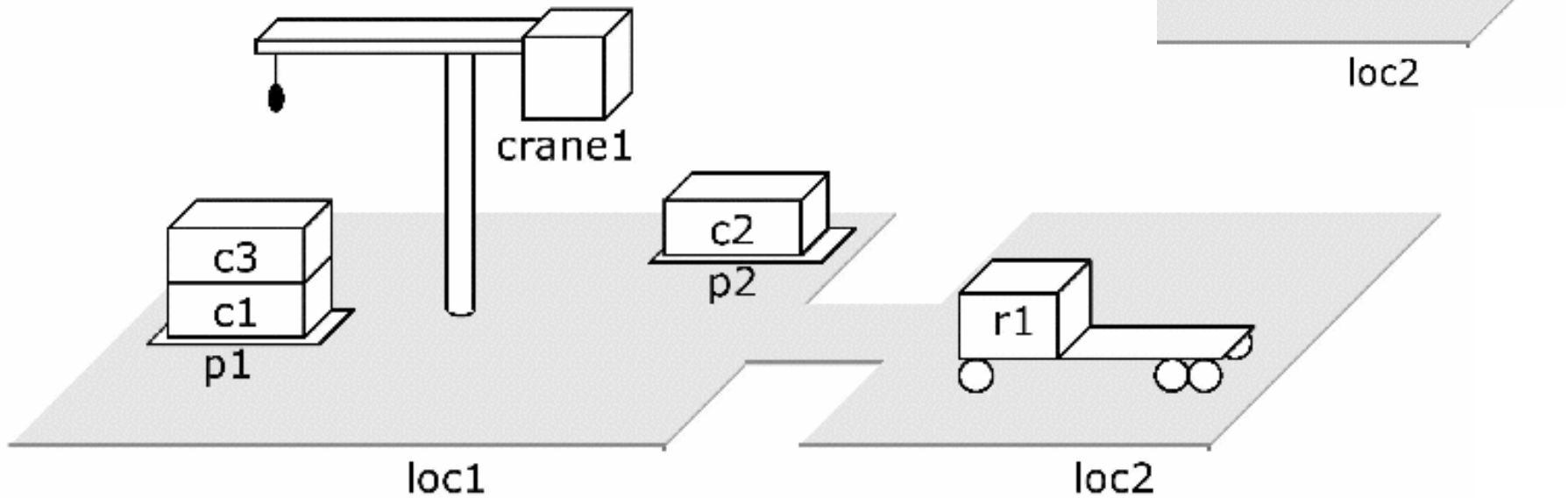
Plans and Solutions

- *Plan*: any sequence of actions $\sigma = \langle a_1, a_2, \dots, a_n \rangle$ 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, \dots, 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

Example

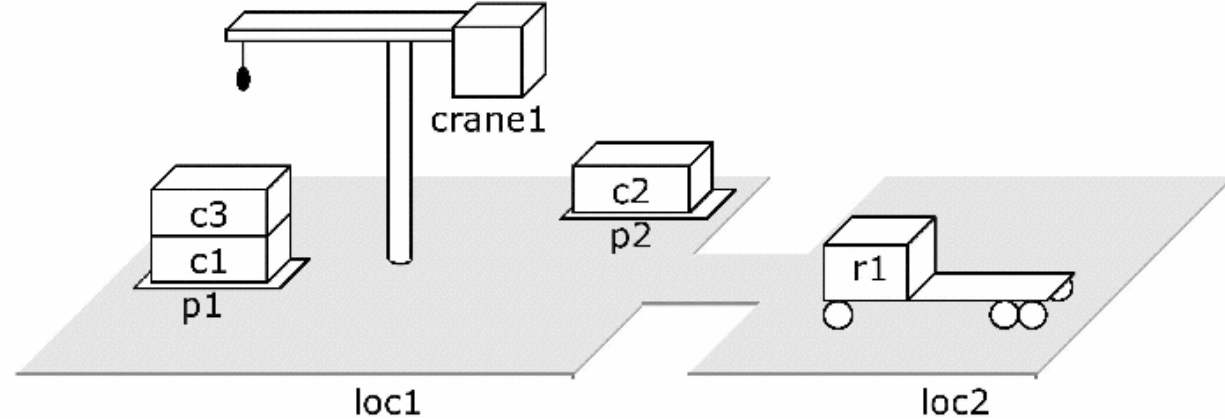
- Let $P_1 = (O, s_1, g_1)$, where
 - O is the set of operators given earlier

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



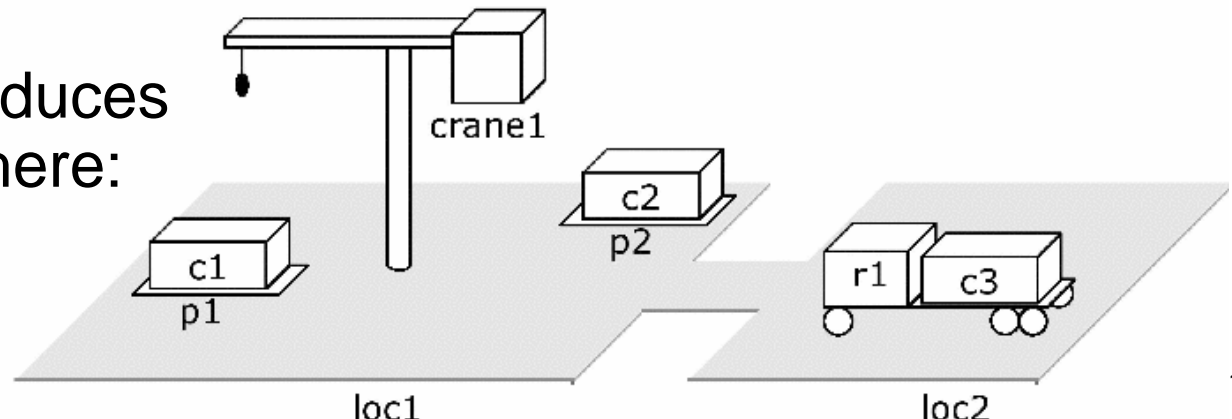
$$s_1 = \{ \text{attached}(p1, \text{loc1}), \text{in}(c1, p1), \text{in}(c3, p1), \text{top}(c3, p1), \text{on}(c3, c1), \text{on}(c1, \text{pallet}), \text{attached}(p2, \text{loc1}), \text{in}(c2, p2), \text{top}(c2, p2), \text{on}(c2, \text{pallet}), \text{belong}(\text{crane1}, \text{loc1}), \text{empty}(\text{crane1}),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

Example (cont.)

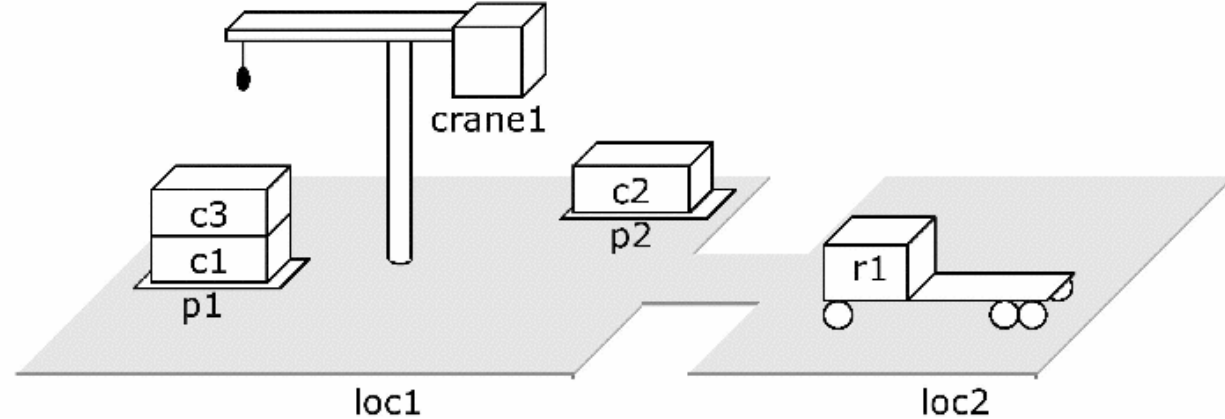


- Here are three solutions for P_1 :
 - $\langle \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$
 - $\langle \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$
 - $\langle \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$

- Each of them produces the state shown here:

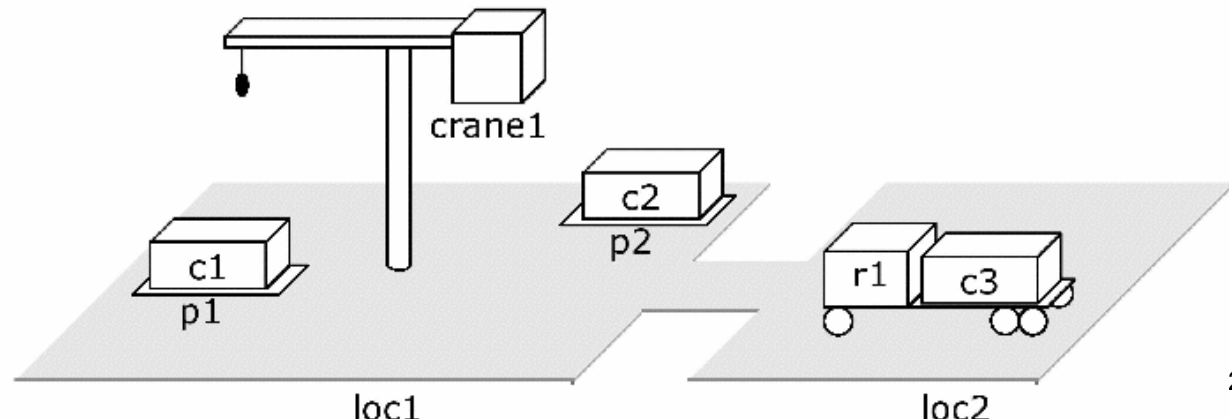


Example (cont.)



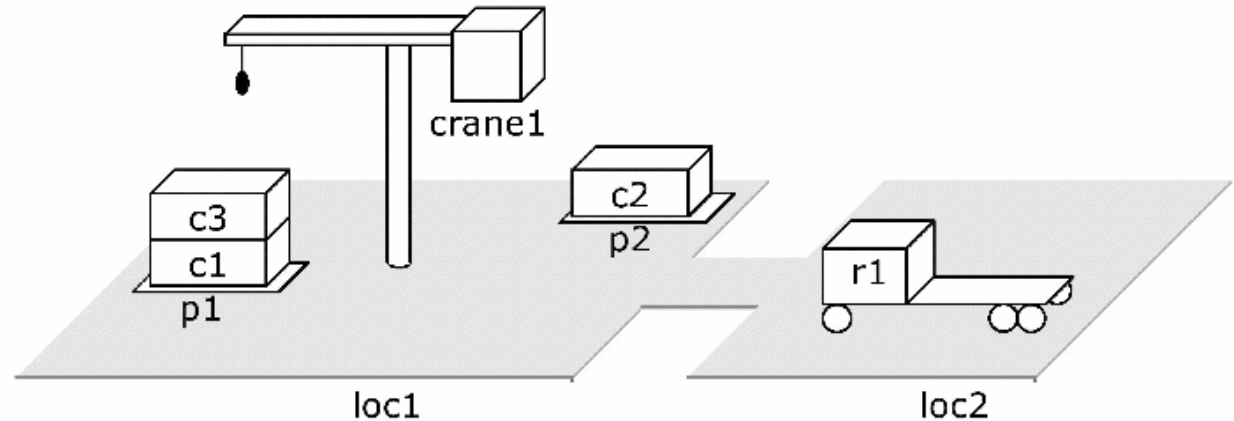
- First is *redundant*: can remove actions and still have a solution
 - $\langle \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$
 - $\langle \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$
 - $\langle \text{move}(\text{r1}, \text{loc2}, \text{loc1}), \text{take}(\text{crane1}, \text{loc1}, \text{c3}, \text{c1}, \text{p1}), \text{load}(\text{crane1}, \text{loc1}, \text{c3}, \text{r1}), \text{move}(\text{r1}, \text{loc1}, \text{loc2}) \rangle$

- The 2nd and 3rd are *irredundant* and *shortest*



2. Set-Theoretic Representation

Like classical representation, but restricted to propositional logic



- States:

- Instead of a collection of ground atoms ...

$\{on(c1,pallet), on(c1,r1), on(c1,c2), \dots, at(r1,l1), at(r1,l2), \dots\}$

... use a collection of propositions (boolean variables):

$\{on-c1-pallet, on-c1-r1, on-c1-c2, \dots, at-r1-l1, at-r1-l2, \dots\}$

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), ¬empty(k), ¬in(c, p), ¬top(c, p), ¬on(c, d), top(d, p)
```

take all of
the operator
instances,

e.g., this one

```
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

```
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 $c = |\{\text{constant symbols}\}|$

3. State-Variable Representation

- Non-fluents (properties that don't change) are ground relations:
e.g., $\text{adjacent}(\text{loc1}, \text{loc2})$
- 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

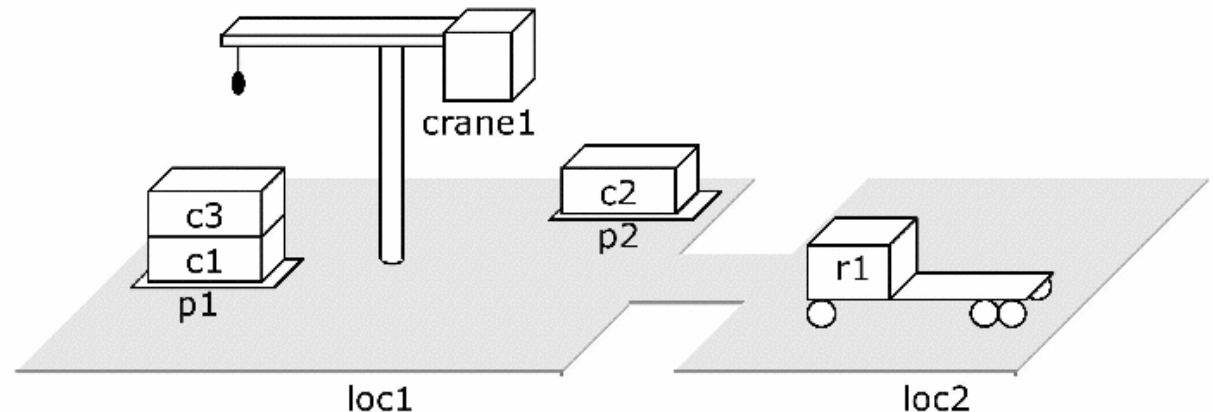
$\text{move}(r, l, m)$

;; robot r at location l moves to an adjacent location m

precond: $\text{rloc}(r) = l, \text{adjacent}(l, m)$

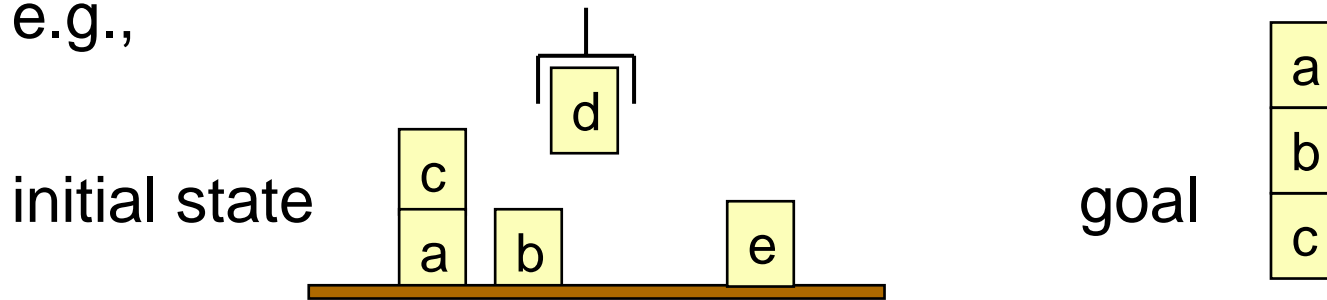
effects: $\text{rloc}(r) \leftarrow m$

$\{\text{top}(p1)=c3,$
 $\text{cpos}(c3)=c1,$
 $\text{cpo}(c1)=\text{pallet},$
 $\text{holding}(\text{crane1})=\text{nil},$
 $\text{rloc}(r1)=\text{loc2},$
 $\text{loaded}(r1)=\text{nil}, \dots\}$



Example: The Blocks World

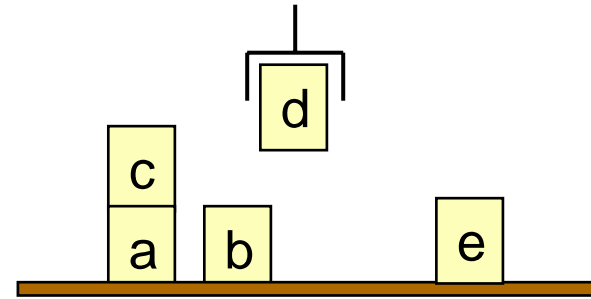
- Infinitely wide table, finite number of children's blocks
- Ignore where a block is located on the table
- A block can sit on the table or on another block
- Want to move blocks from one configuration to another
 - e.g.,



- 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:
 - $\text{ontable}(x)$ - block x is on the table
 - $\text{on}(x,y)$ - block x is on block y
 - $\text{clear}(x)$ - block x has nothing on it
 - $\text{holding}(x)$ - the robot hand is holding block x
 - handempty - the robot hand isn't holding anything



Classical Operators

unstack(x,y)

Precond: $\text{on}(x,y)$, $\text{clear}(x)$, handempty

Effects: $\sim\text{on}(x,y)$, $\sim\text{clear}(x)$, $\sim\text{handempty}$,
 $\text{holding}(x)$, $\text{clear}(y)$

stack(x,y)

Precond: $\text{holding}(x)$, $\text{clear}(y)$

Effects: $\sim\text{holding}(x)$, $\sim\text{clear}(y)$,
 $\text{on}(x,y)$, $\text{clear}(x)$, handempty

pickup(x)

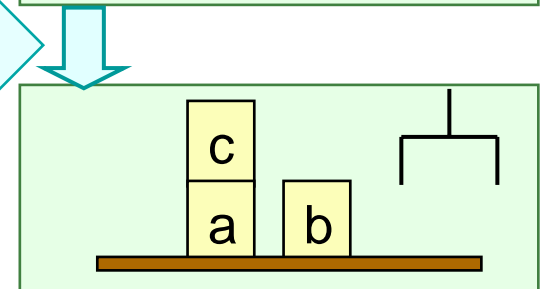
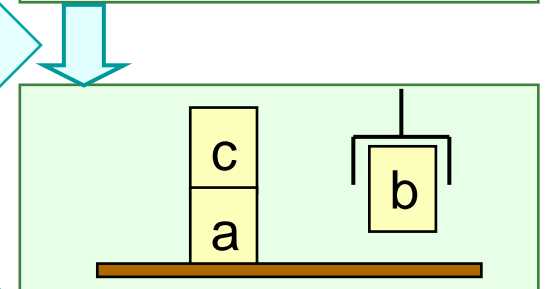
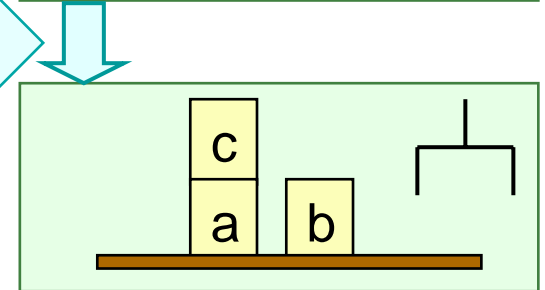
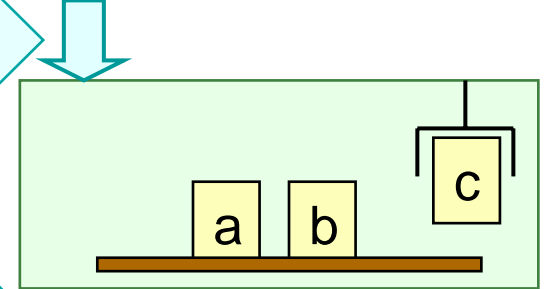
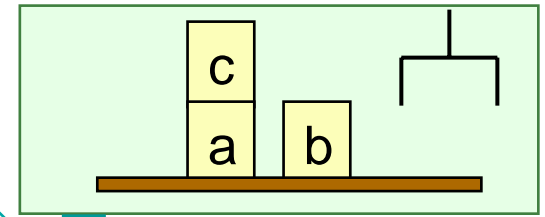
Precond: $\text{ontable}(x)$, $\text{clear}(x)$, handempty

Effects: $\sim\text{ontable}(x)$, $\sim\text{clear}(x)$,
 $\sim\text{handempty}$, $\text{holding}(x)$

putdown(x)

Precond: $\text{holding}(x)$

Effects: $\sim\text{holding}(x)$, $\text{ontable}(x)$,
 $\text{clear}(x)$, handempty

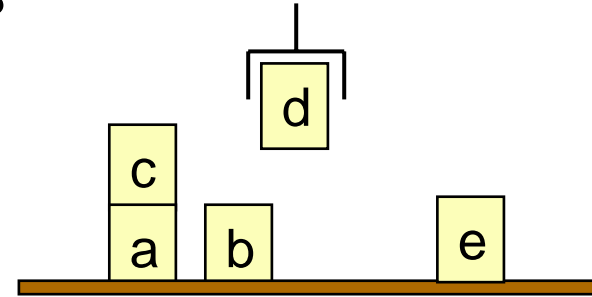


2. Example Set-Theoretic Representation

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

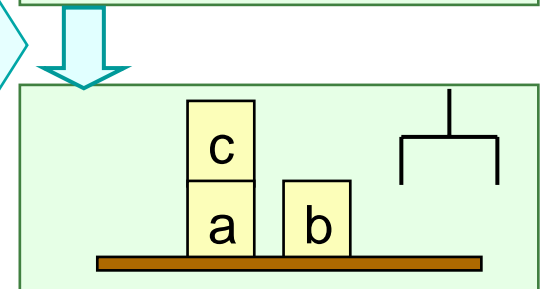
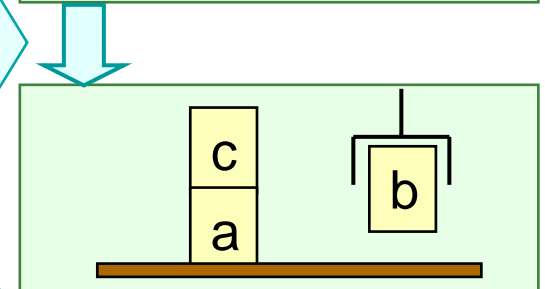
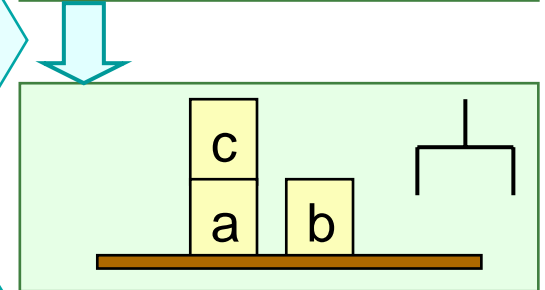
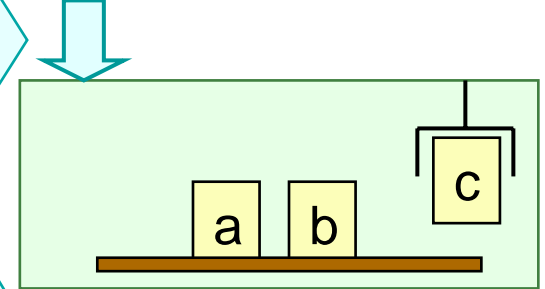
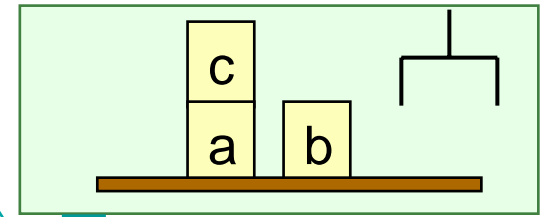
putdown-c

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:

$\text{pos}(x) = y$ if block x is on block y

$\text{pos}(x) = \text{table}$ if block x is on the table

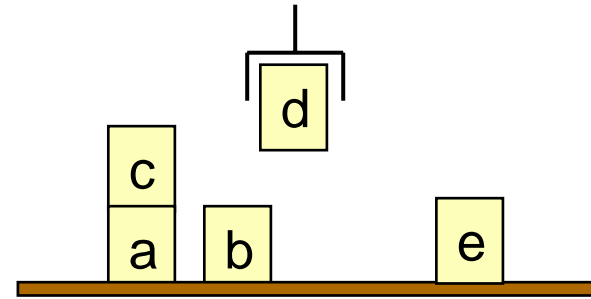
$\text{pos}(x) = \text{nil}$ if block x is being held

$\text{clear}(x) = 1$ if block x has nothing on it

$\text{clear}(x) = 0$ if block x is being held or has a block on it

$\text{holding} = x$ if the robot hand is holding block x

$\text{holding} = \text{nil}$ if the robot hand is holding nothing

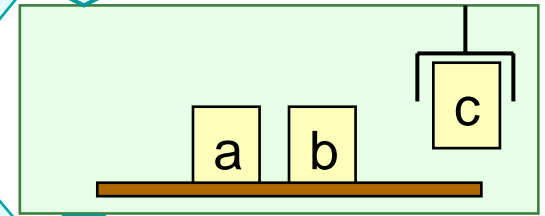
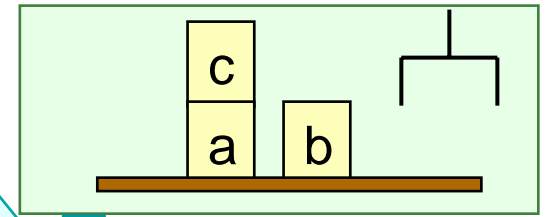


State-Variable Operators

unstack(x : block, y : block)

Precond: $\text{pos}(x)=y$, $\text{clear}(y)=0$, $\text{clear}(x)=1$, $\text{holding}=\text{nil}$

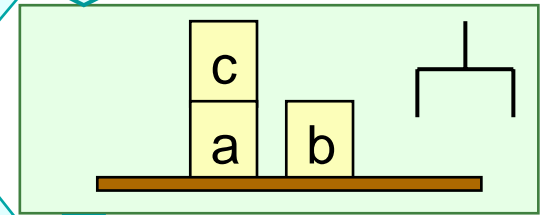
Effects: $\text{pos}(x)=\text{nil}$, $\text{clear}(x)=0$, $\text{holding}=x$, $\text{clear}(y)=1$



stack(x : block, y : block)

Precond: $\text{holding}=x$, $\text{clear}(x)=0$, $\text{clear}(y)=1$

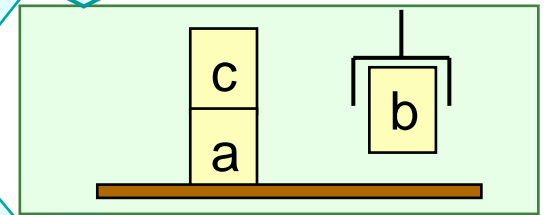
Effects: $\text{holding}=\text{nil}$, $\text{clear}(y)=0$, $\text{pos}(x)=y$, $\text{clear}(x)=1$



pickup(x : block)

Precond: $\text{pos}(x)=\text{table}$, $\text{clear}(x)=1$, $\text{holding}=\text{nil}$

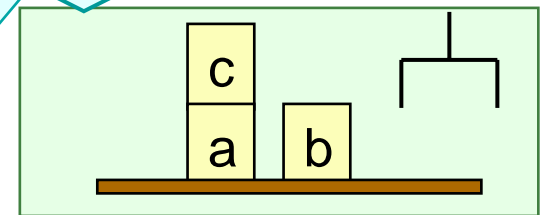
Effects: $\text{pos}(x)=\text{nil}$, $\text{clear}(x)=0$, $\text{holding}=x$



putdown(x : block)

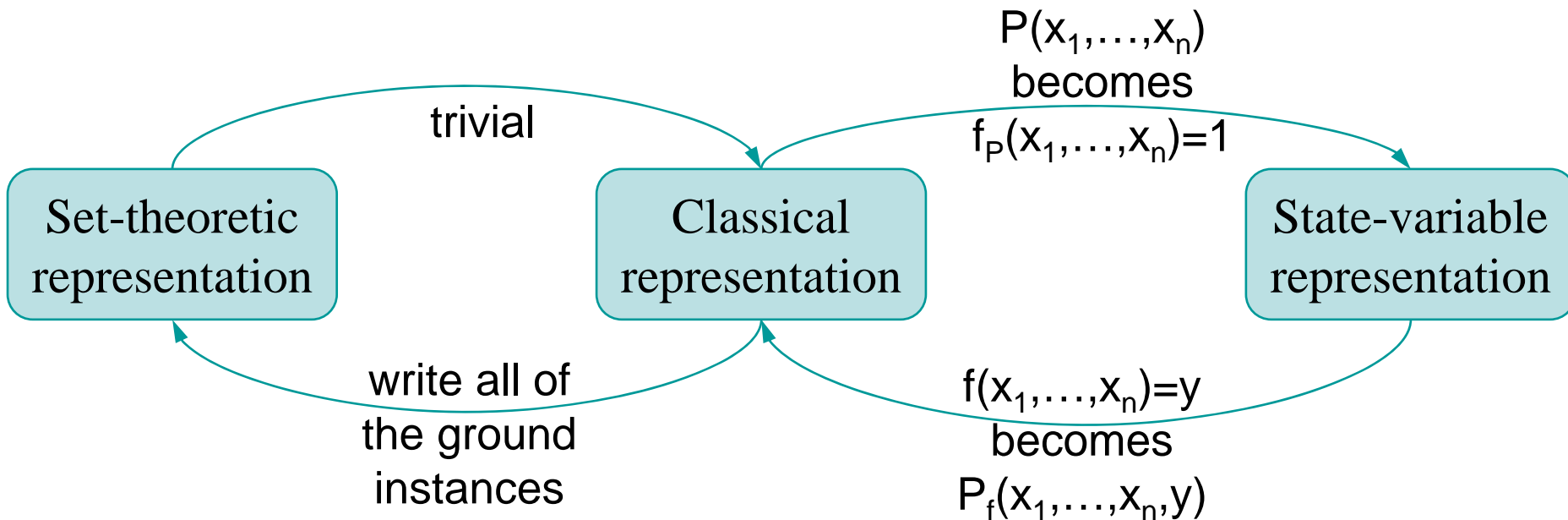
Precond: $\text{holding}=x$

Effects: $\text{holding}=\text{nil}$, $\text{pos}(x)=\text{table}$, $\text{clear}(x)=1$



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)



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
 - Equivalent to classical representation in expressive power
 - Less natural for logicians, more natural for engineers
 - Useful in non-classical planning problems as a way to handle numbers, functions, time

Richer Specification Languages: ADL

- The previous representations were so-called “STRIPS” representations.
- 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

Compiling to Canonical Action Rep'n

PROS & CONS:

It is possible to compile down ADL actions into STRIPS actions

- Quantification is written as conjunctions/disjunctions over finite universes
- Actions with conditional effects are compiled into multiple (exponentially more) actions without conditional effects
- Actions with disjunctive effects are compiled into multiple actions, each of which take one of the disjuncts as their preconditions
- (Domain axioms can be compiled down into 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