Planning and Optimization

X1. Hands-On and Repetition

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Introduction

Hands-On: Outline for this week

Working with an existing planning system (Fast Downward).

- Domain modeling
- Recognizing the difference: blind vs. informed planning
- Implementation in Fast Downward

Hands-On: Overview

Chapter overview: hands-on

- 1. The Planning Domain Definition Language (PDDL)
- 2. Getting to Know a Planner
- 3. Heuristics
- 4. A* search algorithm

PDDL

Representation of State Spaces

Representation of State Spaces

- explicit graphs
- black box
- declarative representations

In this Course: Declarative Representations

- compact description of state space as input to algorithms
  $\rightsquigarrow$ state space exponentially larger than input
- algorithms operate directly on compact description

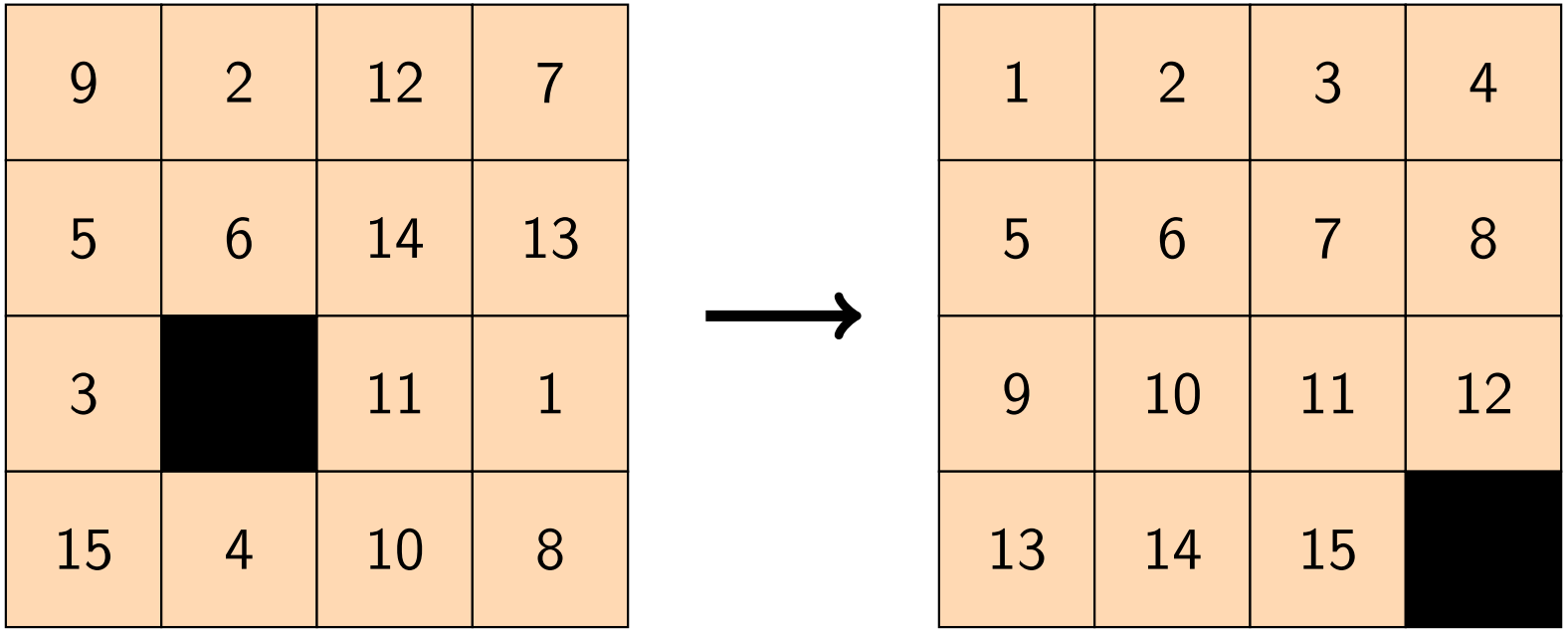
$\rightsquigarrow$ allows automatic reasoning about problem (abstractions etc.)

Representation of State Spaces

PDDL: Planning Domain Definition Language

- PDDL is the standard language used in practice to describe planning tasks.
- descriptions in (restricted) predicate logic instead of propositional logic ($\rightsquigarrow$ even more compact)
- There exist defined PDDL fragments for STRIPS and ADL; many planners only support the STRIPS fragment.
- In this week: restriction to STRIPS

Illustrating Example: 15-Puzzle



15-Puzzle in PDDL

Example: 15-Puzzle in PDDL

Hands-On

Hands-On

clone the course repository

```
hg clone https://bitbucket.org/aibasel/planopt-hs17
```

update the course repository

```
cd planopt-hs17
hg pull -u
```

compile the planner

```
cd hands-on-1/fast-downward
./build.py
```

work on the hands-on exercises

- evaluate and modify the 15-puzzle
- model your own domain