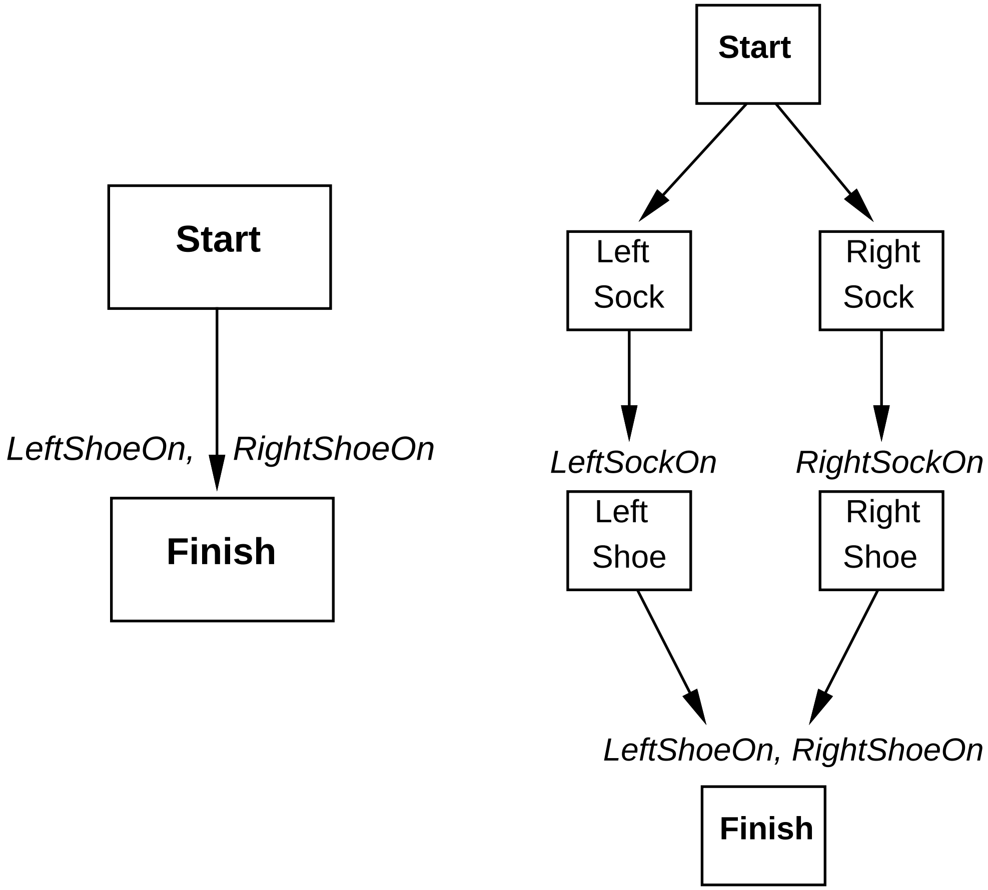
PARTIAL-ORDER PLANNING

Partial Order Planning

- The answer to the problem we ended the last lecture with is to use partial order planning.
- Basically this gives us a way of checking before adding an action to the plan that it doesn't mess up the rest of the plan.
- The problem is that in this recursive process, we don't know what the rest of the plan is.
- Need a new representation *partially ordered plans*.

Representation

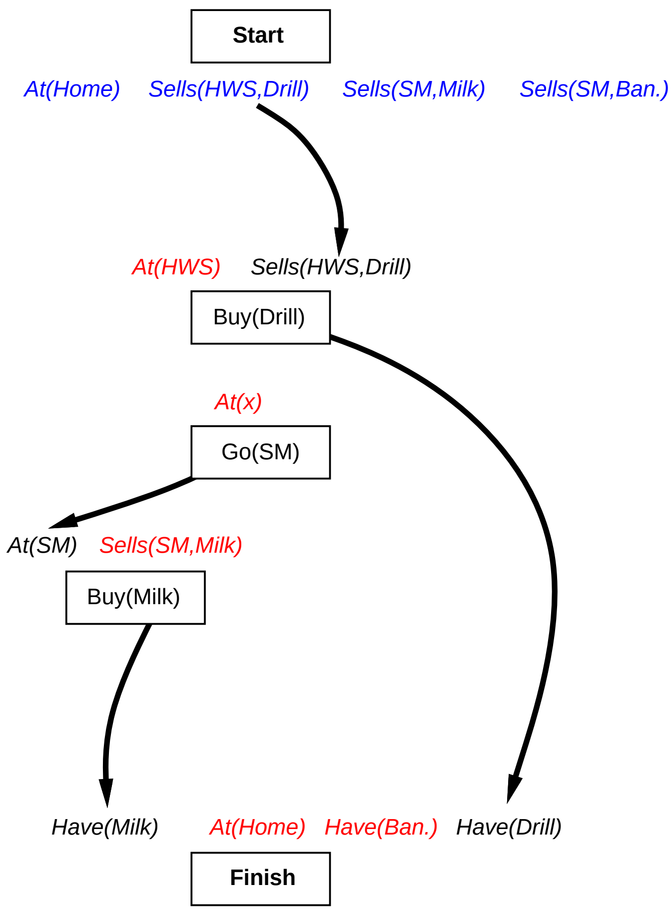


Partially ordered plans

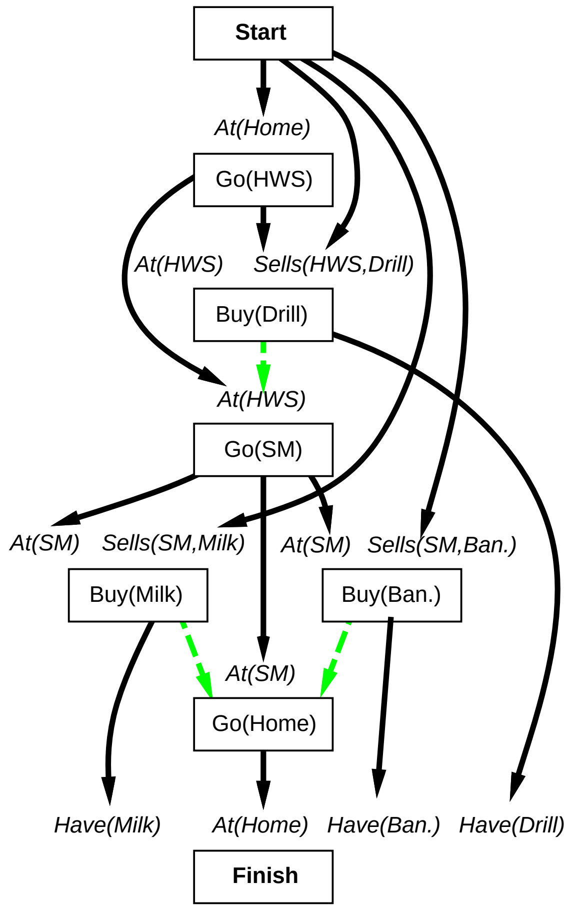
- *Partially ordered* collection of steps with
  - *Start* step has the initial state description as its effect
  - *Finish* step has the goal description as its precondition
  - *causal links* from outcome of one step to precondition of another
  - *temporal ordering* between pairs of steps
- *Open condition* = precondition of a step not yet causally linked
- A plan is *complete* iff every precondition is achieved
- A precondition is *achieved* iff it is the effect of an earlier step and no *possibly intervening* step undoes it

Plan construction

Plan construction (2)



Plan construction (3)



Planning process

- Operators on partial plans:
  - *add a link* from an existing action to an open condition
  - *add a step* to fulfill an open condition
  - *order* one step wrt another to remove possible conflicts
- Gradually move from incomplete/vague plans to complete, correct plans
- Backtrack if an open condition is unachievable or if a conflict is unresolvable

POP algorithm

function POP(*initial*, *goal*, *operators*) **returns** *plan*

plan ← MAKE-MINIMAL-PLAN(*initial*, *goal*)
loop do
  if SOLUTION?(*plan*) **then return** *plan*
  S_{need}, c ← SELECT-SUBGOAL(*plan*)
  CHOOSE-OPERATOR(*plan*, *operators*, S_{need}, c)
  RESOLVE-THREATS(*plan*)
end

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function SELECT-SUBGOAL(*plan*) **returns** S_{need}, c

pick a plan step S_{need} from STEPS(*plan*)
  with a precondition c that has not been achieved
return S_{need}, c

procedure CHOOSE-OPERATOR(*plan*, *operators*, S_{need}, c)

choose a step S_{add} from *operators* or STEPS(*plan*) that has c as an effect
if there is no such step **then fail**
add the causal link $S_{add} \xrightarrow{c} S_{need}$ to LINKS(*plan*)
add the ordering constraint $S_{add} \prec S_{need}$ to ORDERINGS(*plan*)
if S_{add} is a newly added step from *operators* **then**
  add S_{add} to STEPS(*plan*)
  add $Start \prec S_{add} \prec Finish$ to ORDERINGS(*plan*)

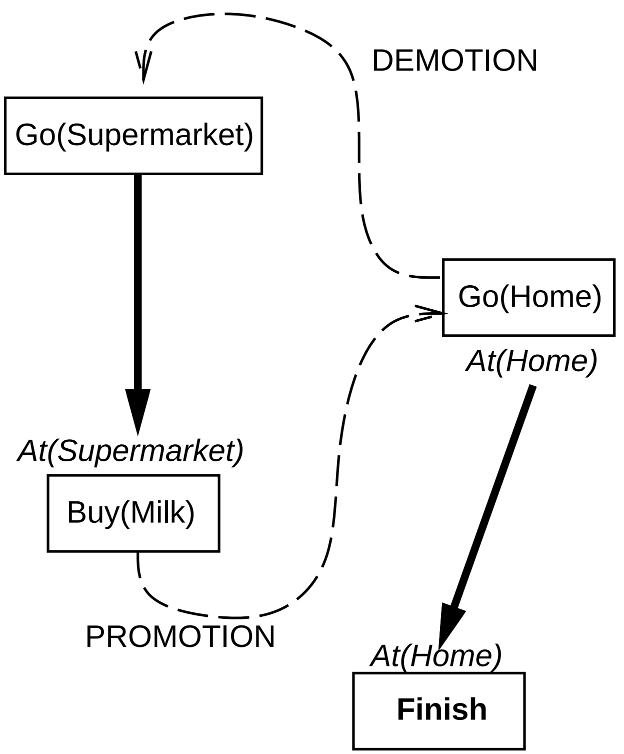
---

procedure RESOLVE-THREATS(*plan*)

for each S_{threat} that threatens a link $S_i \xrightarrow{c} S_j$ in LINKS(*plan*) **do**
  choose either
    Demotion: Add $S_{threat} \prec S_i$ to ORDERINGS(*plan*)
    Promotion: Add $S_j \prec S_{threat}$ to ORDERINGS(*plan*)
  if not CONSISTENT(*plan*) **then fail**
end

Clobbering

- A *clobberer* is a potentially intervening step that destroys the condition achieved by a causal link. E.g., $Go(Home)$ clobbers $At(Supermarket)$:



Demotion: put before $Go(Supermarket)$

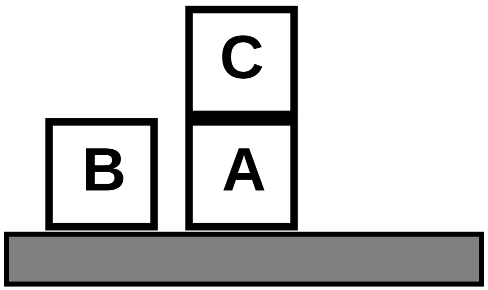
Promotion: put after $Buy(Milk)$

Properties of POP

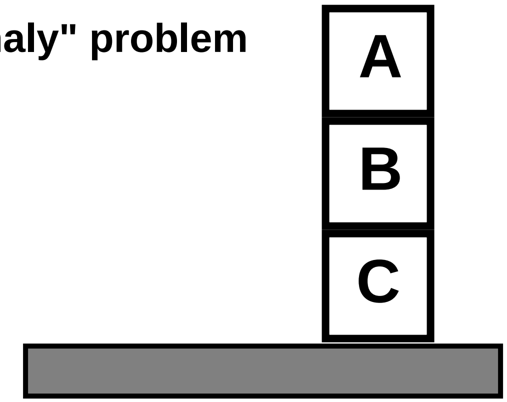
- Nondeterministic algorithm: backtracks at *choice* points on failure:
  - choice of S_{add} to achieve S_{need}
  - choice of demotion or promotion for clobberer
  - selection of S_{need} is irrevocable
- POP is sound, complete, and *systematic* (no repetition)
- Extensions for disjunction, universals, negation, conditionals
- Can be made efficient with good heuristics derived from problem description
- Particularly good for problems with many loosely related subgoals

Example

"Sussman anomaly" problem



Start State



Goal State

Clear(x) On(x,z) Clear(y)

PutOn(x,y)

~On(x,z) ~Clear(y)
Clear(z) On(x,y)

Clear(x) On(x,z)

PutOnTable(x)

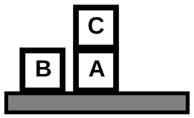
~On(x,z) Clear(z) On(x,Table)

+ several inequality constraints

Example (2)

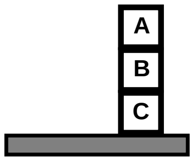
START

On(C,A) On(A,Table) Cl(B) On(B,Table) Cl(C)

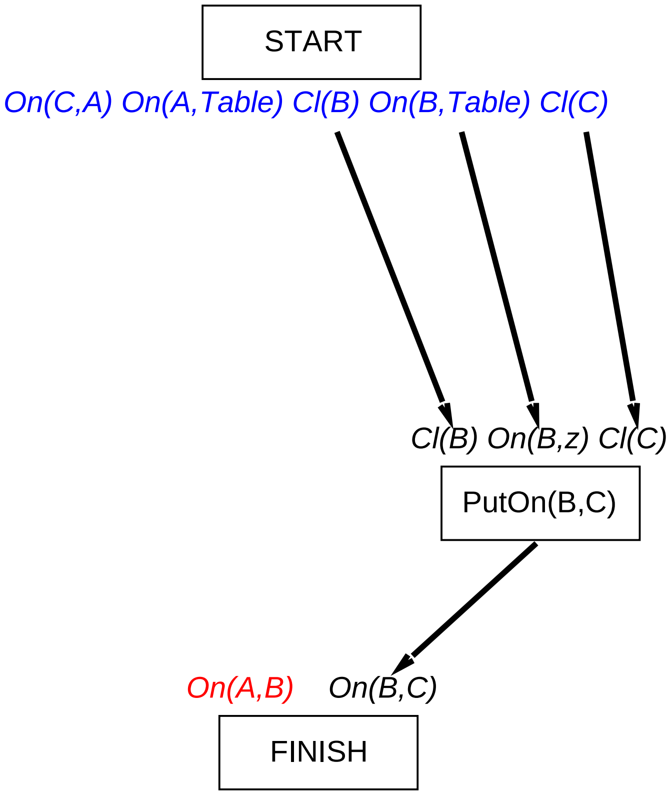


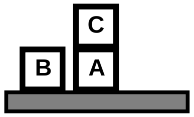
On(A,B) *On(B,C)*

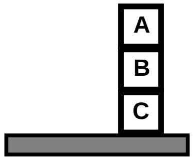
FINISH



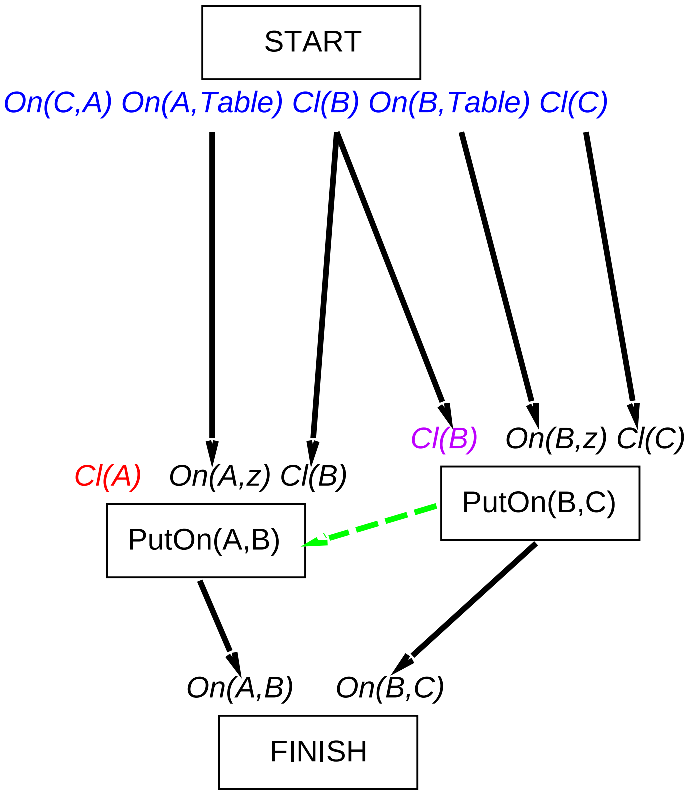
Example (3)

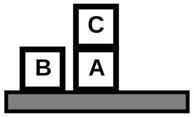

START
On(C,A) On(A,Table) Cl(B) On(B,Table) Cl(C)
Cl(B) On(B,z) Cl(C)
PutOn(B,C)
On(A,B) On(B,C)
FINISH


C
B
A

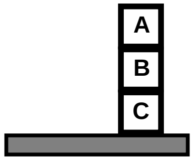

A
B
C

Example (4)

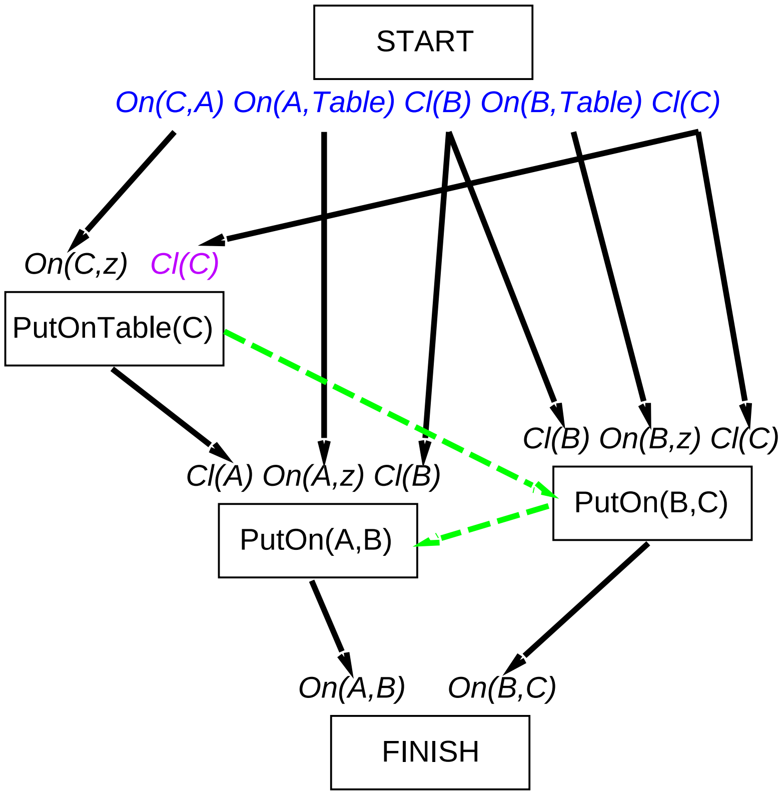


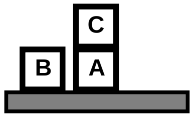


PutOn(A,B)
clobbers Cl(B)
=> order after
PutOn(B,C)



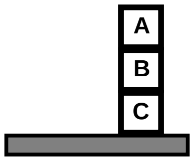
Example (5)





PutOn(A,B) clobbers Cl(B) => order after PutOn(B,C)

PutOn(B,C) clobbers Cl(C) => order after PutOnTable(C)



Summary

- This lecture has looked at a more advanced approach to planning.
  - Partial order planning
- This requires a new way of looking at the world, but the payoff is a more robust approach.
- We also looked at the POP algorithm, ...
- ...and saw how it could solve the Sussman anomaly.