Announcements

- **Project 0: Python Tutorial**
  - Due tomorrow!
  - There is a lab tomorrow from 3pm-5pm in Soda 275
  - The lab time is optional, but P0 itself is not
  - On submit, you should get email from the autograder

- **Project 1: Search**
  - On the web today
  - Start early and ask questions. It’s longer than most!

- **Self-Diagnostic on web**

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CS 188: Artificial Intelligence
Fall 2010

Lecture 2: Queue-Based Search
8/31/2010

Dan Klein – UC Berkeley
Multiple slides from Stuart Russell, Andrew Moore
Today

- Agents that Plan Ahead
- Search Problems
- Uninformed Search Methods (part review for some)
  - Depth-First Search
  - Breadth-First Search
  - Uniform-Cost Search
- Heuristic Search Methods (new for all)
  - Greedy Search

Reflex Agents

- Reflex agents:
  - Choose action based on current percept (and maybe memory)
  - May have memory or a model of the world's current state
  - Do not consider the future consequences of their actions
  - Act on how the world IS
- Can a reflex agent be rational?

[demo: reflex optimal / loop]
Goal Based Agents

- Goal-based agents:
  - Plan ahead
  - Ask “what if”
  - Decisions based on (hypothesized) consequences of actions
  - Must have a model of how the world evolves in response to actions
  - Act on how the world WOULD BE

Search Problems

- A search problem consists of:
  - A state space
  - A successor function
  - A start state and a goal test
  - A solution is a sequence of actions (a plan) which transforms the start state to a goal state
Example: Romania

- State space:
  - Cities
- Successor function:
  - Go to adj city with cost = dist
- Start state:
  - Arad
- Goal test:
  - Is state == Bucharest?
- Solution?

State Space Graphs

- State space graph: A mathematical representation of a search problem
  - For every search problem, there's a corresponding state space graph
  - The successor function is represented by arcs
- We can rarely build this graph in memory (so we don’t)

Ridiculously tiny search graph for a tiny search problem
State Space Sizes?

- Search Problem: Eat all of the food
- Pacman positions: $10 \times 12 = 120$
- Food count: 30

Search Trees

- A search tree:
  - This is a “what if” tree of plans and outcomes
  - Start state at the root node
  - Children correspond to successors
  - Nodes contain states, correspond to PLANS to those states
  - For most problems, we can never actually build the whole tree
Another Search Tree

- **Search:**
  - Expand out possible plans
  - Maintain a *fringe* of unexpanded plans
  - Try to expand as few tree nodes as possible

General Tree Search

```plaintext
function TREE-Search(problem, strategy) returns a solution, or failure
initialize the search tree using the initial state of problem
loop do
  if there are no candidates for expansion then return failure
  choose a leaf node for expansion according to strategy
  if the node contains a goal state then return the corresponding solution
  else expand the node and add the resulting nodes to the search tree
end
```

- **Important ideas:**
  - Fringe
  - Expansion
  - Exploration strategy

- **Main question:** which fringe nodes to explore?
Example: Tree Search

State Graphs vs. Search Trees

We construct both on demand – and we construct as little as possible.

Each NODE in in the search tree is an entire PATH in the problem graph.
Review: Depth First Search

Strategy: expand deepest node first
Implementation: Fringe is a LIFO stack

Review: Breadth First Search

Strategy: expand shallowest node first
Implementation: Fringe is a FIFO queue
Search Algorithm Properties

- **Complete?** Guaranteed to find a solution if one exists?
- **Optimal?** Guaranteed to find the least cost path?
- **Time complexity?**
- **Space complexity?**

Variables:

<p>| | |</p>
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>$n$</td>
<td>Number of states in the problem</td>
</tr>
<tr>
<td>$b$</td>
<td>The average branching factor $B$ (the average number of successors)</td>
</tr>
<tr>
<td>$C^*$</td>
<td>Cost of least cost solution</td>
</tr>
<tr>
<td>$s$</td>
<td>Depth of the shallowest solution</td>
</tr>
<tr>
<td>$m$</td>
<td>Max depth of the search tree</td>
</tr>
</tbody>
</table>

DFS

<table>
<thead>
<tr>
<th>Algorithm</th>
<th>Complete</th>
<th>Optimal</th>
<th>Time</th>
<th>Space</th>
</tr>
</thead>
<tbody>
<tr>
<td>DFS</td>
<td>Depth First Search</td>
<td>N</td>
<td>N</td>
<td>Infinite</td>
</tr>
</tbody>
</table>

- Infinite paths make DFS incomplete...
- How can we fix this?
DFS

- With cycle checking, DFS is complete.*

When is DFS optimal?

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</tr>
</thead>
<tbody>
<tr>
<td>DFS w/ Path Checking</td>
<td>Y</td>
<td>N</td>
<td>$O(b^{m+1})$</td>
<td>$O(b^m)$</td>
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</tbody>
</table>

* Or graph search – next lecture.

BFS

- When is BFS optimal?

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<tr>
<td>BFS</td>
<td>Y</td>
<td>N*</td>
<td>$O(b^{s+1})$</td>
<td>$O(b^s)$</td>
</tr>
</tbody>
</table>
Comparisons

- When will BFS outperform DFS?
- When will DFS outperform BFS?

Iterative Deepening

Iterative deepening uses DFS as a subroutine:

1. Do a DFS which only searches for paths of length 1 or less.
2. If "1" failed, do a DFS which only searches paths of length 2 or less.
3. If "2" failed, do a DFS which only searches paths of length 3 or less.
   ....and so on.

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<td>O(bm)</td>
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<td>Y</td>
<td>N*</td>
<td>O(b^{r+1})</td>
<td>O(b^r)</td>
</tr>
<tr>
<td>ID</td>
<td>Y</td>
<td>N*</td>
<td>O(b^{s+1})</td>
<td>O(bs)</td>
</tr>
</tbody>
</table>
Notice that BFS finds the shortest path in terms of number of transitions. It does not find the least-cost path. We will quickly cover an algorithm which does find the least-cost path.

**Uniform Cost Search**

Expand cheapest node first:
Fringe is a priority queue
### Priority Queue Refresher

- A priority queue is a data structure in which you can insert and retrieve (key, value) pairs with the following operations:

<table>
<thead>
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<th>Operation</th>
<th>Description</th>
</tr>
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<tbody>
<tr>
<td><code>pq.push(key, value)</code></td>
<td>inserts (key, value) into the queue.</td>
</tr>
<tr>
<td><code>pq.pop()</code></td>
<td>returns the key with the lowest value, and removes it from the queue.</td>
</tr>
</tbody>
</table>

- You can decrease a key's priority by pushing it again
- Unlike a regular queue, insertions aren't constant time, usually $O(\log n)$
- We'll need priority queues for cost-sensitive search methods

### Uniform Cost Search

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<td>Y</td>
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<td>$O(b^s)$</td>
</tr>
<tr>
<td>UCS</td>
<td>Y*</td>
<td>Y</td>
<td>$O(b^{\epsilon})$</td>
<td>$O(b^{C*})$</td>
</tr>
</tbody>
</table>

* UCS can fail if actions can get arbitrarily cheap
Uniform Cost Issues

- Remember: explores increasing cost contours
- The good: UCS is complete and optimal!
- The bad:
  - Explores options in every "direction"
  - No information about goal location

Search Heuristics

- Any *estimate* of how close a state is to a goal
- Designed for a particular search problem
- Examples: Manhattan distance, Euclidean distance
Heuristics

Best First / Greedy Search

- Expand the node that seems closest...

- What can go wrong?

[demo: greedy]
Best First / Greedy Search

- A common case:
  - Best-first takes you straight to the (wrong) goal

- Worst-case: like a badly-guided DFS in the worst case
  - Can explore everything
  - Can get stuck in loops if no cycle checking

- Like DFS in completeness (finite states w/ cycle checking)

Search Gone Wrong?