Partial Order Planning

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PARTIAL ORDER PLAN

Any planning algorithm that can place into a plan without specifying which comes first is called a partial order plan

ADVANTAGES

- DIVIDE & CONQUER

  Works on several subgoals independently, solves them with several subproblems and then combines the subplans.

- FLEXIBILITY

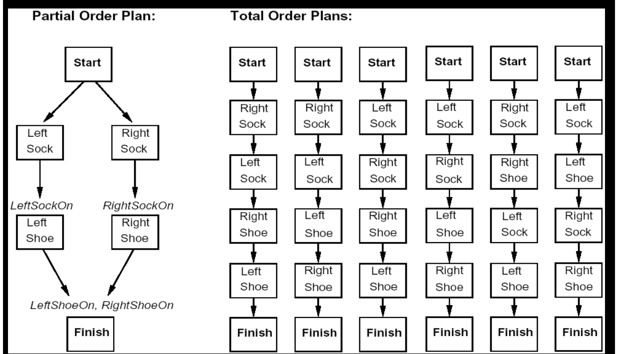
  The planner can work on important decisions first, rather than being forced to work on steps in chronological order

- LEAST COMMITMENT

  We can delay our choice during search

  e.g. do not commit to an order of actions until it is required

Total-Order vs Partial-Order Plans



POP ALGORITHM

- Formulate planning as a state space search problem

➢**States:** Unfinished plan
➢**Action:** Steps added for completion
➢**Goal:** Finished plan

➢Nodes are partial plans
➢Arcs/Transitions are plan refinements
➢Solution is a node (not a path).

COMPONENTS OF POP

- Actions
- Ordering Constraints
- Causal Links
- Open Preconditions

➢A Solution is consistent plan with no open preconditions

CONSISTENT PLAN

- **Cycle Checking**: By ordering Constraint
- **Conflict Resolvation**: Placing new action outside **protection interval**

➢A plan is **Complete** iff all preconditions are achieved

Partial Plan Representation

- Plan = (A, O, L), where
  - A: set of actions in the plan
  - O: *temporal orderings* between actions (a < b)
  - L: *causal links* linking actions via a literal
- Causal Link: $Ap \xrightarrow{Q} Ac$

  Action Ac (consumer) has precondition Q that is established in the plan by Ap (producer).

move-a-from-b-to-table $\xrightarrow{\text{(clear b)}}$ move-c-from-d-to-b

Threats to causal links

Step A_t <u>threatens</u> link (A_p, Q, A_c) if:

1. A_t has (not Q) as an effect, and
2. A_t could come between A_p and A_c, i.e.

   $O \cup (A_p < A_t < A_c)$ is consistent

What's an example of an action that threatens the link example from the last slide?

Initial Plan

For uniformity, represent initial state and goal with two special actions:

- A_0:
  - no preconditions,
  - initial state as **effects**,
  - must be the **first** step in the plan.
- A_∞:
  - no effects
  - goals as **preconditions**
  - must be the **last** step in the plan.

POP algorithm

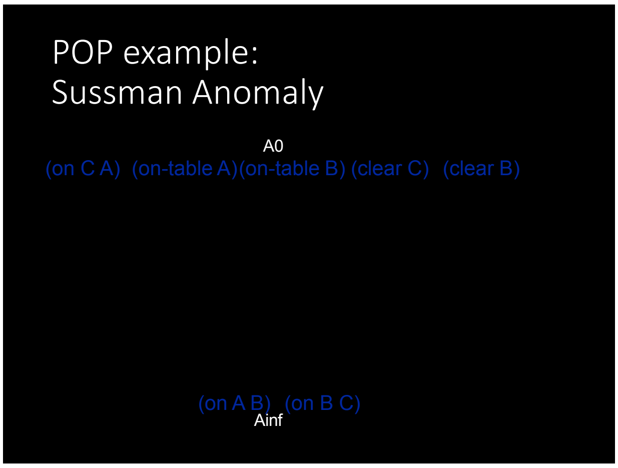
POP((A, O, L), agenda, actions) — Termination
  If agenda = () then return (A, O, L) — Goal Selection
  Pick (Q, a_{need}) from agenda — Action Selection
  a_{add} = **choose**(actions) s.t. $Q \in effects(a_{add})$
  If no such action a_{add} exists, **fail**.
  $L' := L \cup (a_{add}, Q, a_{need})$; $O' := O \cup (a_{add} < a_{need})$
  agenda' := agenda - (Q, a_{need}) — Update goals
  If a_{add} is new, then $A := A \cup a_{add}$ and
    $\forall P \in preconditions(a_{add})$, add (P, a_{add}) to agenda'
  For every action a_t that threatens any causal link (a_p, Q, a_c) in L'
    choose to add $a_t < a_p$ or $a_c < a_t$ to O.
    If neither choice is consistent, **fail**.
  POP((A', O', L'), agenda, actions)

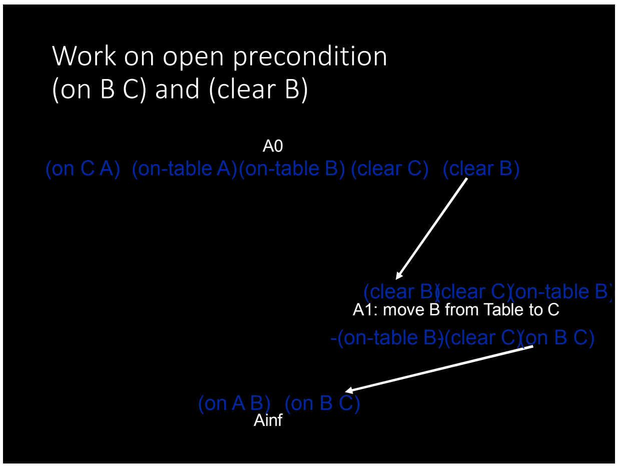
Protect causal links
- Demotion: $a_t < a_p$
- Promotion: $a_c < a_t$

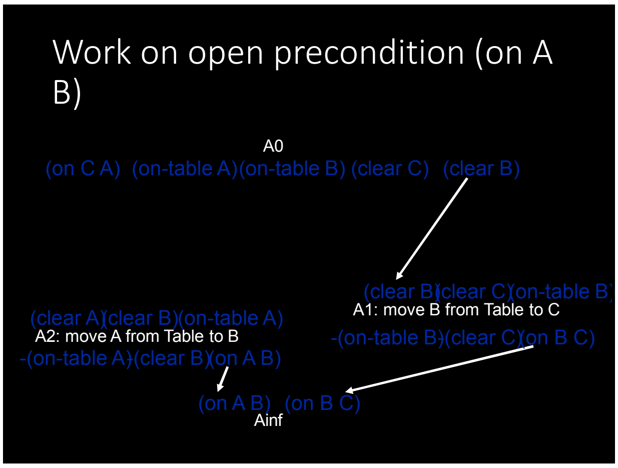
POP

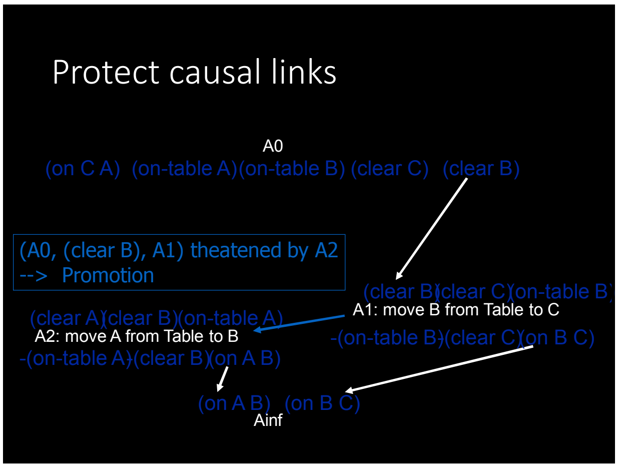
POP is sound and complete

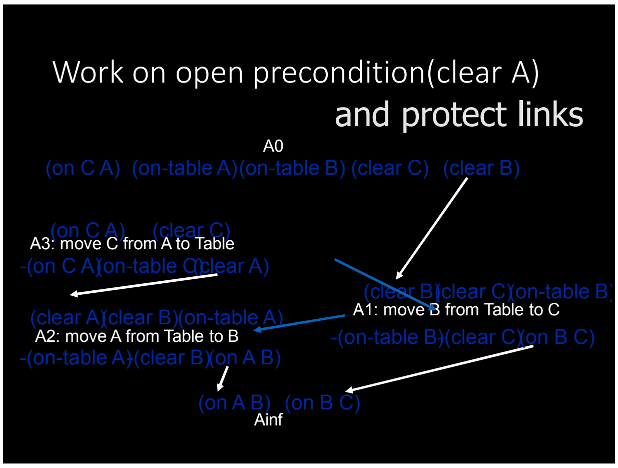
- POP Plan is a solution if:
  - All preconditions are supported (by causal links), i.e., no open conditions.
  - No threats
  - Consistent temporal ordering
- By construction, the POP algorithm reaches a solution plan

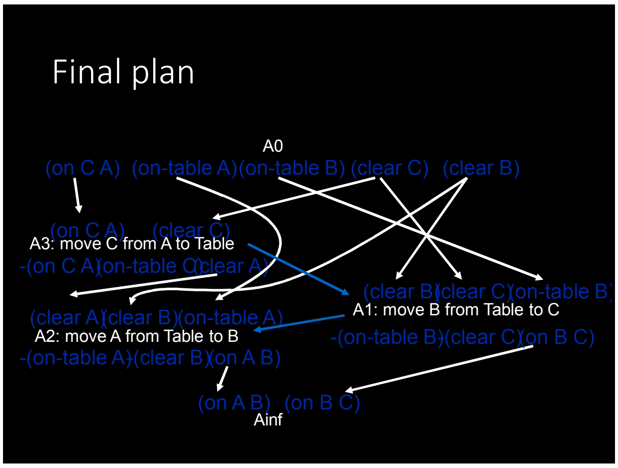

POP example:
Sussman Anomaly
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(on A B) (on B C)
Ainf


Work on open precondition
(on B C) and (clear B)
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(clear B)(clear C)(on-table B)
A1: move B from Table to C
-(on-table B)-(clear C)(on B C)
(on A B) (on B C)
Ainf


Work on open precondition (on A B)
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(clear B)(clear C)(on-table B)
A1: move B from Table to C
-(on-table B)-(clear C)(on B C)
(clear A)(clear B)(on-table A)
A2: move A from Table to B
-(on-table A)-(clear B)(on A B)
(on A B) (on B C)
Ainf


Protect causal links
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(A0, (clear B), A1) theatened by A2
--> Promotion
(clear B)(clear C)(on-table B)
A1: move B from Table to C
-(on-table B)-(clear C)(on B C)
(clear A)(clear B)(on-table A)
A2: move A from Table to B
-(on-table A)-(clear B)(on A B)
(on A B) (on B C)
Ainf


Work on open precondition(clear A)
and protect links
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(on C A) (clear C)
A3: move C from A to Table
-(on C A)(on-table C)(clear A)
(clear B)(clear C)(on-table B)
A1: move B from Table to C
-(on-table B)-(clear C)(on B C)
(clear A)(clear B)(on-table A)
A2: move A from Table to B
-(on-table A)-(clear B)(on A B)
(on A B) (on B C)
Ainf


Final plan
A0
(on C A) (on-table A)(on-table B) (clear C) (clear B)
(on C A) (clear C)
A3: move C from A to Table
-(on C A)(on-table C)(clear A)
(clear B)(clear C)(on-table B)
A1: move B from Table to C
-(on-table B)-(clear C)(on B C)
(clear A)(clear B)(on-table A)
A2: move A from Table to B
-(on-table A)-(clear B)(on A B)
(on A B) (on B C)
Ainf

Plartial-Order Planning vs State-Space Planning

Complexity: $O(b^n)$ worst-case

- Non-deterministic choices (n):
  - ProgWS, RegWS: n = |actions|
  - POP: n = |preconditions| + |link protection|
  - Generally an action has several preconditions
- Branching factor (b)

  POP has smaller b:
  - No backtrack due to goal ordering
  - Least commitment: no premature step ordering
    - Does POP make the least possible amount of commitment?

PROPERTIES OF POP ALGORITHM

- POP is
  - Sound
  - Complete
  - Systematic (no repetition)
- Extension for
  - Disjunction
  - Universals
  - Negation
  - Conditionals
- Currently not the most efficient method
  - Very sensitive to subgoal ordering

HEURISTICS FOR POP

- The number of distinct open preconditions
- Select precondition that can be satisfied in fewest number of ways
- Relax heuristics
- Planning Graph