



UCPOP

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Background

- Most planners at the time had one of two limitations:
 - Only using STRIPS notation
 - Output is a totally ordered plan
- Learned previously about POP which uses STRIPS to give a partially ordered plan



Action Description Language (ADL)

- Expands on STRIPS to allow more features
- Existential (\exists) and Universal (\forall) Quantifiers
- Equality (=) and inequality (\neq)

MOV B(l)

ADD : At(B, l)

At(z, l) $\forall z \mid \text{In}(z) \wedge z \neq B$

DELETE : At(B, m)

At(z, m) $\forall z \mid \text{In}(z) \wedge z \neq B$



Introducing UCPOP

- Universal Conditional Partial Order Planner
- Uses ADL instead of STRIPS
- Produces a nonlinear plan
- Can solve more problems than POP because it uses ADL
- Allows for conditionals and quantifiers



How it works

- Very similar to POP algorithm from last time
 - We must search through ground clauses to find goals, subgoals, and protect causal links
1. Terminate if there's no more goals
 2. Select a goal
 3. Find an operator that gives the effect we're looking for
 4. Generate new subgoals
 5. Protect causal links (Promotion, Demotion, *Separation*)
 6. Recurse



Expanding quantifiers to get ground clauses

- When finding operators, subgoals, we need ground clauses rather than quantifiers
- The universal base Υ gives us a way to expand quantifiers

$$\{\exists x \textit{Above}(x, A), \forall \exists w' \textit{On}(y, w)\}$$

- We can apply Υ to this to receive the following:

$$\{\exists x \textit{Above}(x, A), \exists w' \textit{On}(A, w'), \exists w' \textit{On}(B, w')\}$$



Separation

- Another way besides promotion and demotion to protect causal links
- Given causal link $S_i \xrightarrow{e_i, q} S_j$ with threat S_k , add $\{S_i < S_k < S_j\}$ as a constraint
- Two different ways to separate
 - Add more constraints on existential variables that cause the variables to not interfere thus removing the threat
 - Create a new goal that will separate the conflicting variables when resolved



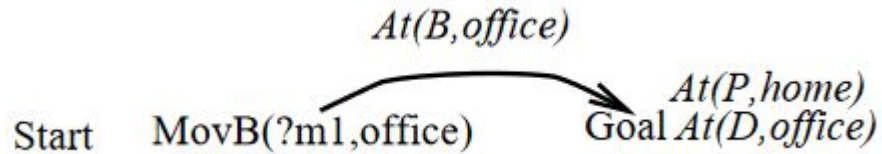
Briefcase Problem

Start *At(P,home)*
 At(B,office)
Goal *At(D,office)*

- Two locations, Home (H) and Office (W)
- Three items, a Paycheck (P) and a dictionary (D), and a Briefcase (B)
- All three items start at home, with the Paycheck inside the Briefcase
- Operators:
 - *MovB(M, L)* which moves the briefcase and everything in it from location M to the location L
 - *PutIn(I, L)* which puts item I in the briefcase at the location L
 - *TakeOut(I)* which takes item I out of the briefcase
- Goal: leave the paycheck at home and take the briefcase and dictionary to the office

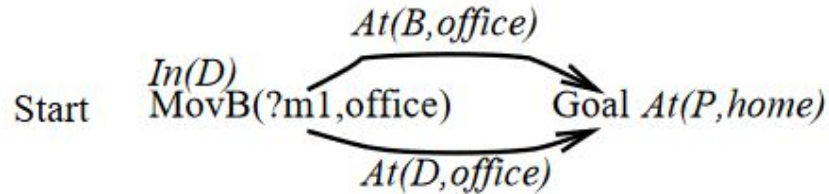
Briefcase Problem (Cont.)

- We select $At(B, Office)$ as the first goal
- Then use $MovB(?m1, office)$ to move the briefcase to the office



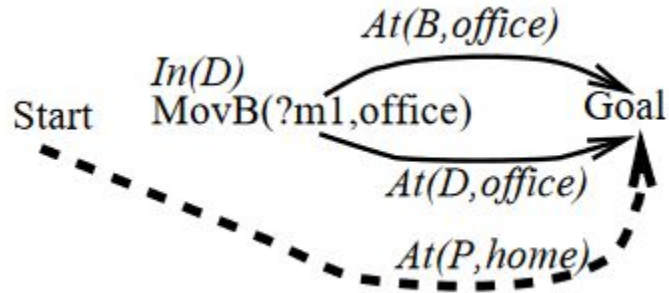
Briefcase Problem (Cont.)

- Next we select $At(D, office)$ as a goal
- We recognize we can solve this with $MovB$, assuming the dictionary is in the briefcase
- $In(D)$ gets added as a subgoal before $MovB$



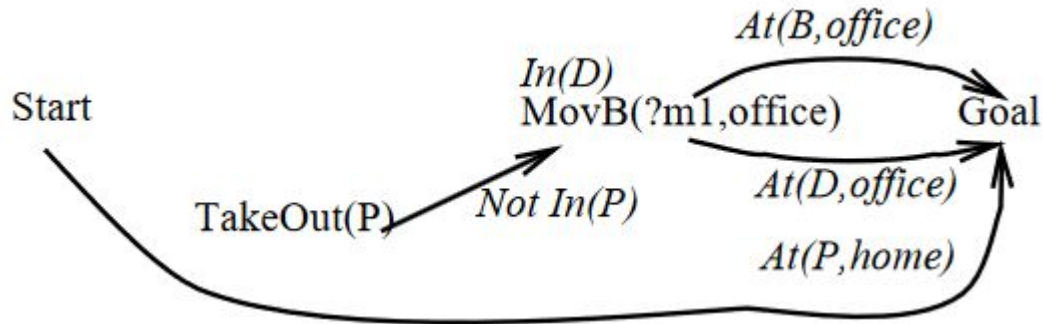
Briefcase Problem (Cont.)

- Next we select $At(P, home)$ as a goal
- This is part of the initial state of the system
- However this causal link is threatened by the $MovB$ step since the paycheck is in the briefcase
- *All items within the briefcase are moved*



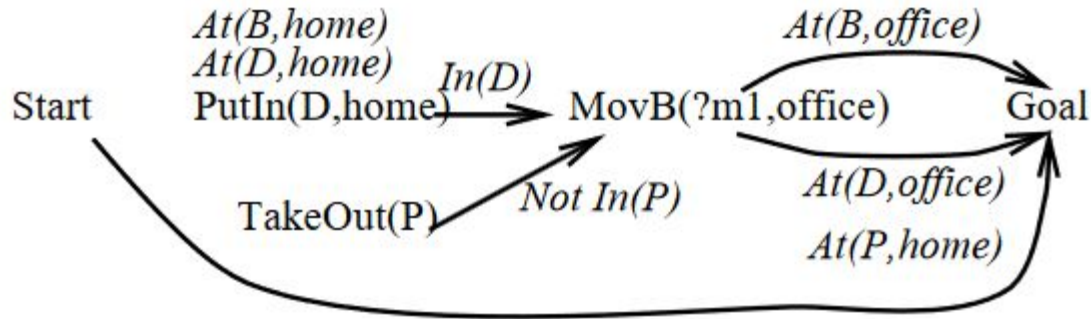
Briefcase Problem (Cont.)

- We add a new subgoal, $\sim \text{In}(P)$ to remove the paycheck from the briefcase
- This is solved by taking the paycheck out of the briefcase before moving it



Briefcase Problem (Cont.)

- We now select $In(D)$ as a goal
- This is solved by putting the dictionary in the briefcase before moving it
- We now have two new goals, B and D must be at home



Briefcase Problem (Cont.)

- We can resolve these last two goals from the initial state of the problem
- ?m1 can be assigned *home*
- The plan is complete!

