

Reinforced Encoding for Planning as SAT

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Planning

- Input:
 - Initial state, goal states, available actions
- Output:
 - A sequence of actions that transforms initial state to goal state
- Classical planning:
 - Deterministic, fully observable, static world
 - Actions are instantaneous
 - Domain-independent techniques

SAS+ format

- Initial state:

| | 1 | 2 | 3 | 4 | 5 | 6 |
|---|----|---|---|---|---|---|
| A | 7 | 0 | 2 | 3 | 5 | 5 |
| B | 4 | 2 | 3 | 1 | 0 | 4 |
| C | 3 | 7 | 2 | 3 | 3 | 1 |
| D | 25 | 2 | 1 | 3 | 5 | 0 |

SAS+ format

- Actions:
 - $(A3 = 7, B1 = 4) \Rightarrow (A3 = 1)$
 - $(D3 = 2, D1 = 6) \Rightarrow (C5 = 1, B2 = 1)$
 - $() \Rightarrow (C1 = 1)$
 - ...
- Goal condition:
 - $D6 = 1$

SAS+ format

- Current state:

| | 1 | 2 | 3 | 4 | 5 | 6 |
|---|----|---|---|---|---|---|
| A | 7 | 0 | 2 | 3 | 5 | 5 |
| B | 4 | 2 | 3 | 1 | 0 | 4 |
| C | 3 | 7 | 2 | 3 | 3 | 1 |
| D | 25 | 2 | 1 | 3 | 5 | 0 |

- Action: $(B4 = 1, C2 = 7) \Rightarrow C5 = 4$

SAS+ format

- Current state:

| | 1 | 2 | 3 | 4 | 5 | 6 |
|---|----|---|---|---|---|---|
| A | 7 | 0 | 2 | 3 | 5 | 5 |
| B | 4 | 2 | 3 | 1 | 0 | 4 |
| C | 3 | 7 | 2 | 3 | 3 | 1 |
| D | 25 | 2 | 1 | 3 | 5 | 0 |

- Action: $(B4 = 1, C2 = 7) \Rightarrow C5 = 4$

SAS+ format

- New state:

| | 1 | 2 | 3 | 4 | 5 | 6 |
|---|----|---|---|---|---|---|
| A | 7 | 0 | 2 | 3 | 5 | 5 |
| B | 4 | 2 | 3 | 1 | 0 | 4 |
| C | 3 | 7 | 2 | 3 | 4 | 1 |
| D | 25 | 2 | 1 | 3 | 5 | 0 |

- Action: $(B4 = 1, C2 = 7) \Rightarrow C5 = 4$

Boolean satisfiability (SAT)

- Input: boolean formula in CNF
- Output: satisfying assignment to variables
OR
„NO“ if no such assignment exists
- NP-complete problem
- Lots of SAT solvers exist
 - Often effective on practical problems

Planning as SAT

- Solving the planning problem using a SAT solver
 - Popular and competitive approach
- Basic idea:
 - For a planning problem P and a number k , we create a boolean formula F , such that
 - F is satisfiable if and only if there is a plan for P that contains k actions (steps)
 - A plan for P of a length k can be constructed from a satisfying assignment to F
 - We increase k until the formula is satisfiable

Parallel plans

- Some actions can be executed simultaneously
- Parallel steps:
 - Actions u and v can be in the same parallel step if
 - Effects of u don't violate preconditions of v and vice versa
 - „For all“ – semantics:
 - Set of actions can be in the same parallel step if *all* orderings of the actions form a valid plan
 - „Exists“ – semantics:
 - Set of actions can be in the same parallel step if *there is* an ordering of the actions that forms a valid plan
 - No longer a „parallel“ semantics

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Parallel plans

- Some actions can be executed simultaneously
- Parallel steps:
 - Actions u and v can be in the same parallel step if
 - Effects of u don't violate preconditions of v and vice versa
 - Increasing planning efficiency
 - Shorter makespan, less SAT solver calls
 - How do we find actions that can be executed together?
 - Sufficient condition:
 - actions are pairwise **independent** (don't share variables)

Parallel plans

- $(A4 = 2, D1 = 3) \Rightarrow (A4 = 3)$
- $(A2 = 3, B1 = 4) \Rightarrow (C1 = 5)$

independent

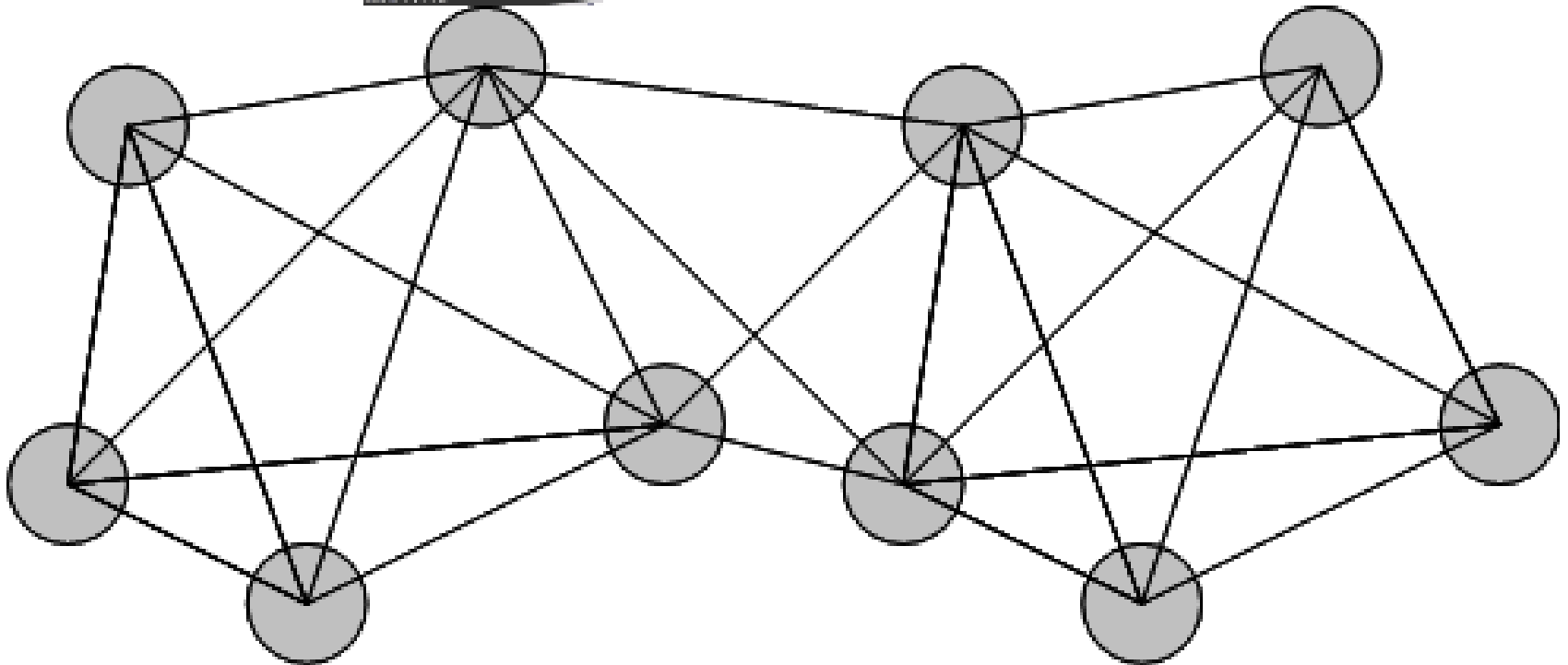
- $(A4 = 2, D1 = 3) \Rightarrow (A4 = 3)$
- $(A2 = 3, B1 = 4) \Rightarrow (D1 = 5)$

NOT independent

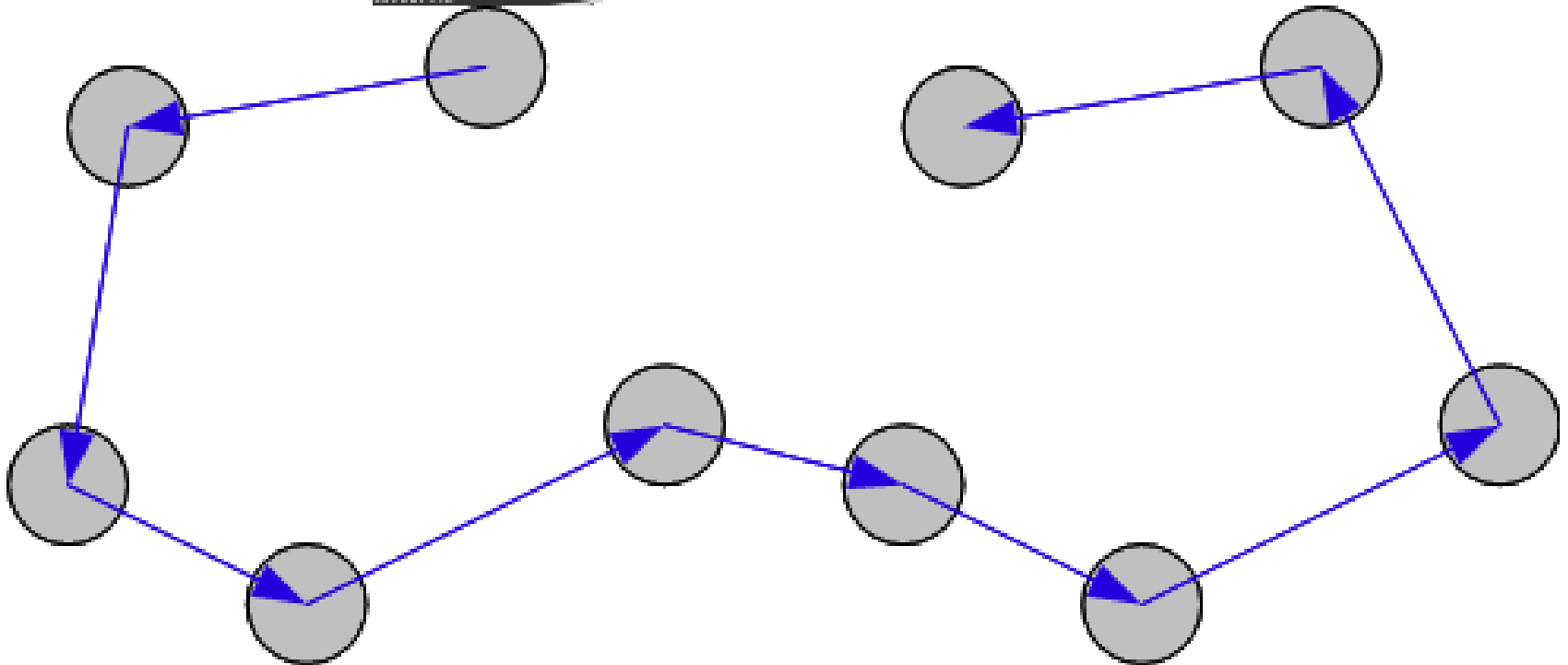
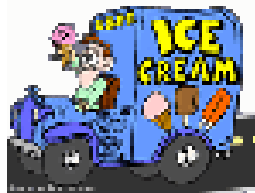
- $(A4 = 2, D1 = 3) \Rightarrow (D1 = 1)$
- $(A4 = 2, B1 = 4) \Rightarrow (B1 = 5)$

NOT independent
but parallelizable

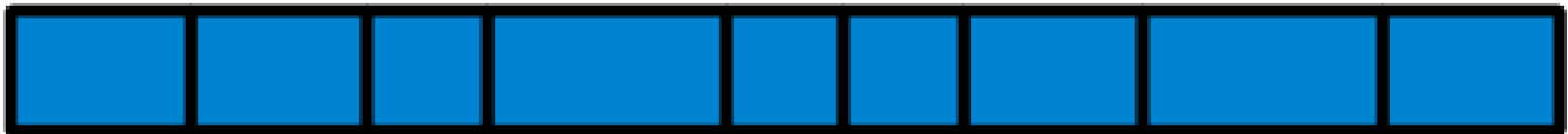
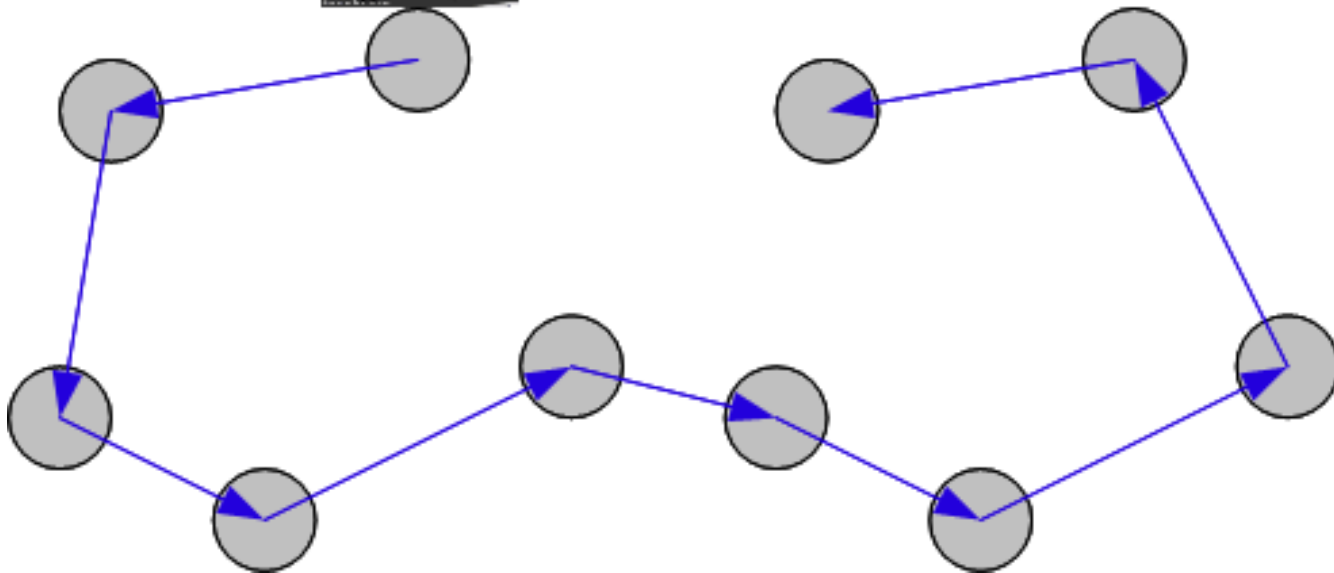
Parallel plans



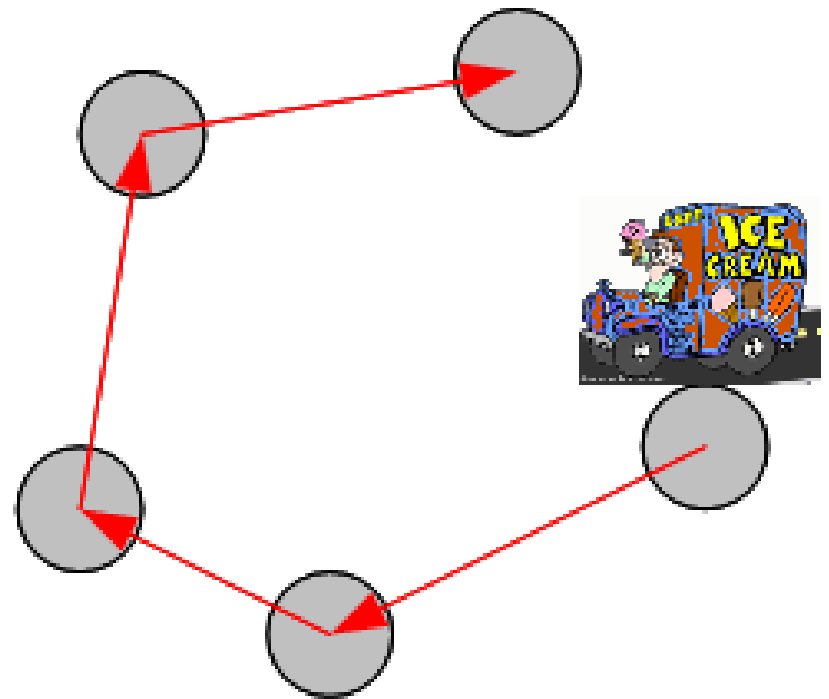
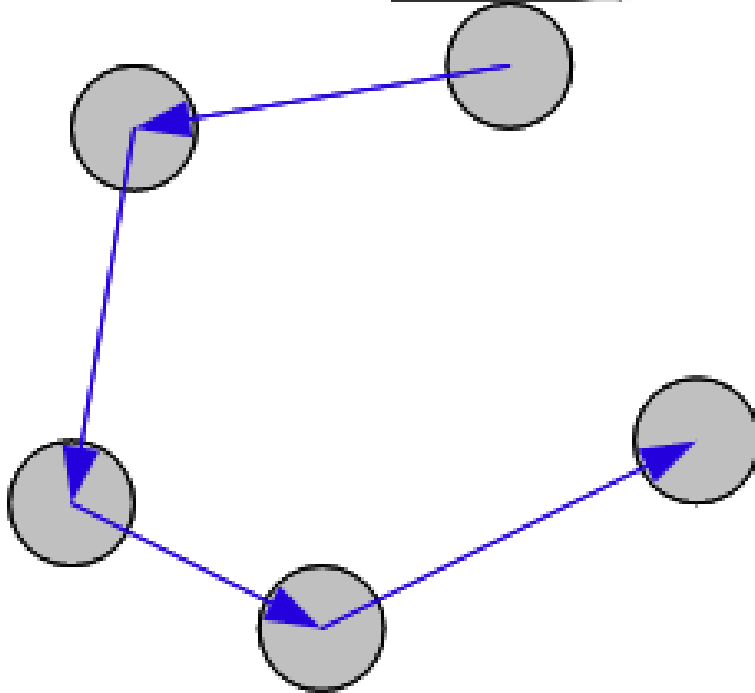
Parallel plans



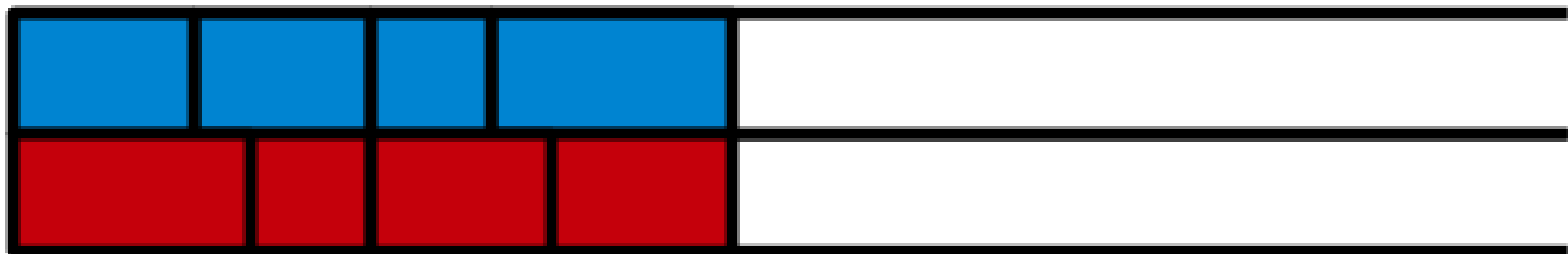
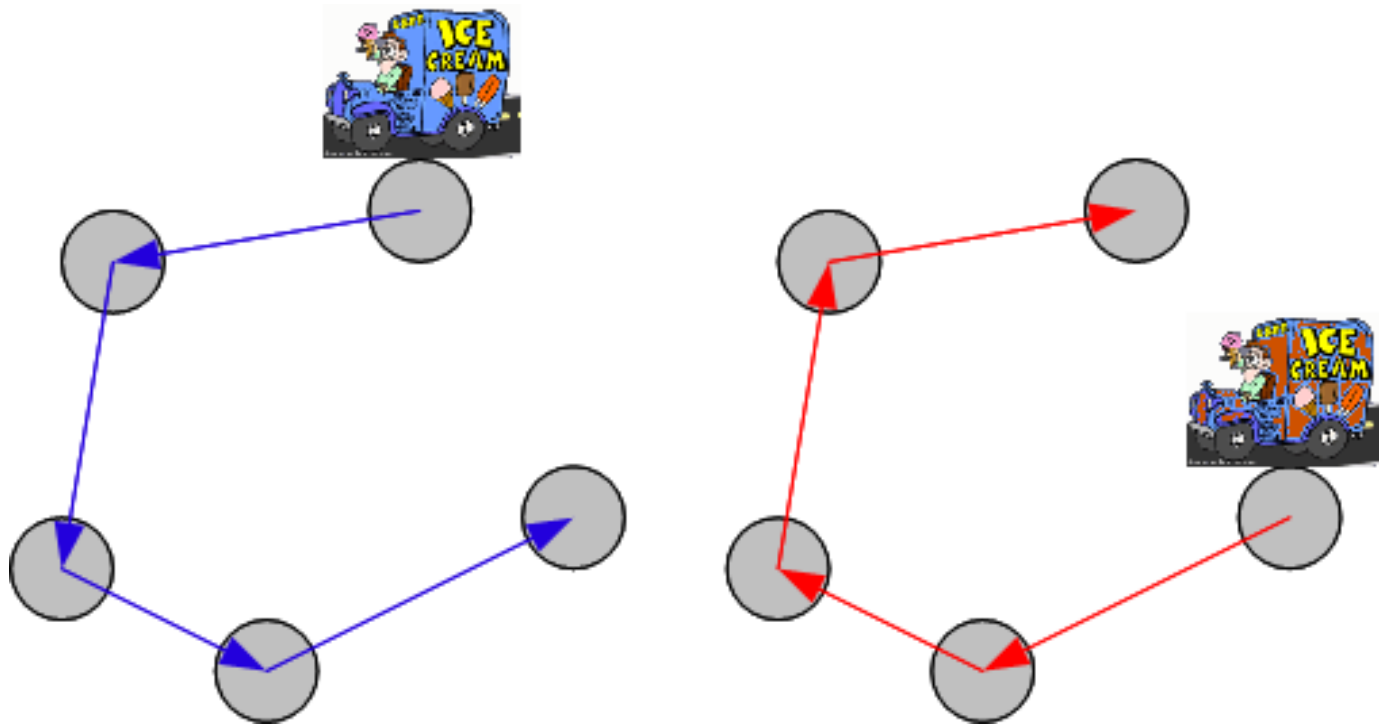
Parallel plans



Parallel plans



Parallel plans



Transitions

- Action can be seen as a set of transitions
- 3 kinds of transitions
 - Active
 - $(A2 = 3, \underline{B2 = 4}) \Rightarrow (\underline{B2 = 5}, C2 = 6)$
 - Prevailing
 - $(\underline{A2 = 3}, B2 = 4) \Rightarrow (B2 = 5, C2 = 6)$
 - Mechanical
 - $(A2 = 3, B2 = 4) \Rightarrow (B2 = 5, \underline{C2 = 6})$

Reinforced encoding

- 3 kinds of SAT variables:
 - **Action variables:** $a_i^t = true$ if
action a_i occurs in the t -th parallel time step
 - **Assignment variables:** $b_{x=v}^t = true$ if
variable x has value v at the end of t -th time step
 - **Transition variables:** $c_{x: d \rightarrow e}^t = true$ if
transition $x: d \rightarrow e$ occurs in the t -th time step
- + clauses ensuring correctness

Reinforced encoding - clauses

1. Only one value to each state variable
 2. Used transitions imply values changes
 3. Transitions' preconditions hold in the previous step
 4. Value changes imply the use of proper transition
 5. Using action imply using all its transitions
 6. Transitions has to be supported by actions
 7. Excluding **compatible** non-independent actions
 8. Encoding the initial state and goal condition
- Usually shorter clauses than with other encodings
 - Sophisticated reductions of the number of clauses

Other SAT encodings

- **Direct encoding**
 - Action based
 - Uses **action** and **assignment** variables
- **SASE encoding**
 - Transition based
 - Uses **action** and **transition** variables
- **$R^2\exists$ -step encoding**
 - Uses different parallel semantics

Experimental results - coverage

| Domain | Dir | SASE | Reinf | $R^2 \exists$ |
|-------------|-----------|-----------|-----------|---------------|
| barman | 4 | 4 | 4 | 8 |
| elevators | 20 | 20 | 20 | 20 |
| floortile | 16 | 11 | 18 | 18 |
| nomystery | 20 | 10 | 20 | 6 |
| openstacks | 0 | 0 | 0 | 15 |
| pareprinter | 20 | 20 | 20 | 20 |
| parking | 0 | 0 | 0 | 0 |
| pegsol | 10 | 6 | 10 | 19 |
| scanalyzer | 14 | 12 | 15 | 9 |
| sokoban | 2 | 2 | 2 | 2 |
| tidybot | 2 | 2 | 2 | 2 |
| transport | 16 | 17 | 18 | 13 |
| visitall | 12 | 9 | 10 | 20 |
| woodworking | 20 | 20 | 20 | 20 |
| Total | 156 | 133 | 159 | 172 |

Conclusions & future work

- New encoding for planning as SAT
 - Outperforms other encodings on some domains
- Combination of *Direct* and *SASE* encoding
 - More variables may pay off
- Future work:
 - Decreasing the number of clauses
 - More compact way of encoding of the action interference constraints