CS540 Introduction to Artificial Intelligence

Young Wu

Based on lecture slides by Jerry Zhu, Yingyu Liang, and Charles Dyer

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Summary

Discussion

Uniformed vs. Informed Search Motivation

- Uninformed search means only the goal G and the successor functions s' are given.
- Informed search means which non-goal states are better is also known.

Heuristic Diagram

Motivation

Uniform Cost Search

- Expand the vertices with the lowest current path cost g (s) first.
- It is BFS with a priority queue based on g(s).
- It is equivalent to BFS if c = 1 is constant on all edges.
- It is also called Dijkstra's Algorithm.

UCS Example 1

UCS Example 1 Diagram

UCS Example 1 Expansion Path Quiz

UCS Example 2

UCS Example 2 Diagram

Uniform Cost Search Performance

- UCS is complete.
- UCS is optimal with any c.

Best First Greedy Search Description

- Expand the vertices with the lowest heuristic cost h(s) first.
- Use a priority queue based on h(s).
- BFGS is not an abbreviation of Best First Greedy Search:
 BFGS is the Broyden Fletcher Goldfarb Shanno algorithm (a version of gradient descent).

Greedy Example 1

Greedy Example 1 Diagram

Greedy Example 2

Greedy Example 2 Diagram

Best First Greedy Search Performance

- Greedy is incomplete.
- Greedy is not optimal.

A Search Description

- Expand the vertices with the lowest total cost g(s) + h(s) first.
- Use a priority queue based on g(s) + h(s).
- A stands for Always be optimistic?

A Search Example 1

A Search Example 1 Diagram

A Search Example 2

A Search Example 2 Diagram

A Search Performance

Discussion

- A is complete.
- A is not optimal.

A Star Search Description

• A* search is A search with an admissible heuristic.

Admissible Heuristic

Definition

 A heuristic is admissible if it never over estimates the true cost.

$$0 \leqslant h(s) \leqslant h^{\star}(s)$$

Admissible Heuristic 8 Puzzle Example Definition

Admissible Heuristic 8 Puzzle Example

A Star Search Example 1

A Star Search Example 1 Diagram

Admissible Heuristic General Example 1

A Search Performance

Discussion

- A^* is complete.
- A^* is optimal.

Iterative Deepening A Star Search

Discussion

- A^* can use a lot of memory.
- Do path checking without expanding any vertex with g(s) + h(s) > 1.
- Do path checking without expanding any vertex with g(s) + h(s) > 2.
- ..
- Do path checking without expanding any vertex with g(s) + h(s) > d.

Iterative Deepening A Star Search Performance

- IDA* is complete.
- IDA* is optimal.
- IDA* is more costly than A^* .

Beam Search

- Version 1: Keep a priority queue with fixed size *k*. Only keep the top *k* vertices and discard the rest.
- Version 2: Only keep the vertices that are at most ε worse than the best vertex in the queue. ε is called the beam width.

Beam Search Performance

Discussion

- Beam is incomplete.
- Beam is not optimal.

Summary

Discussion