

Symbolic Search for Total-Order HTN Planning

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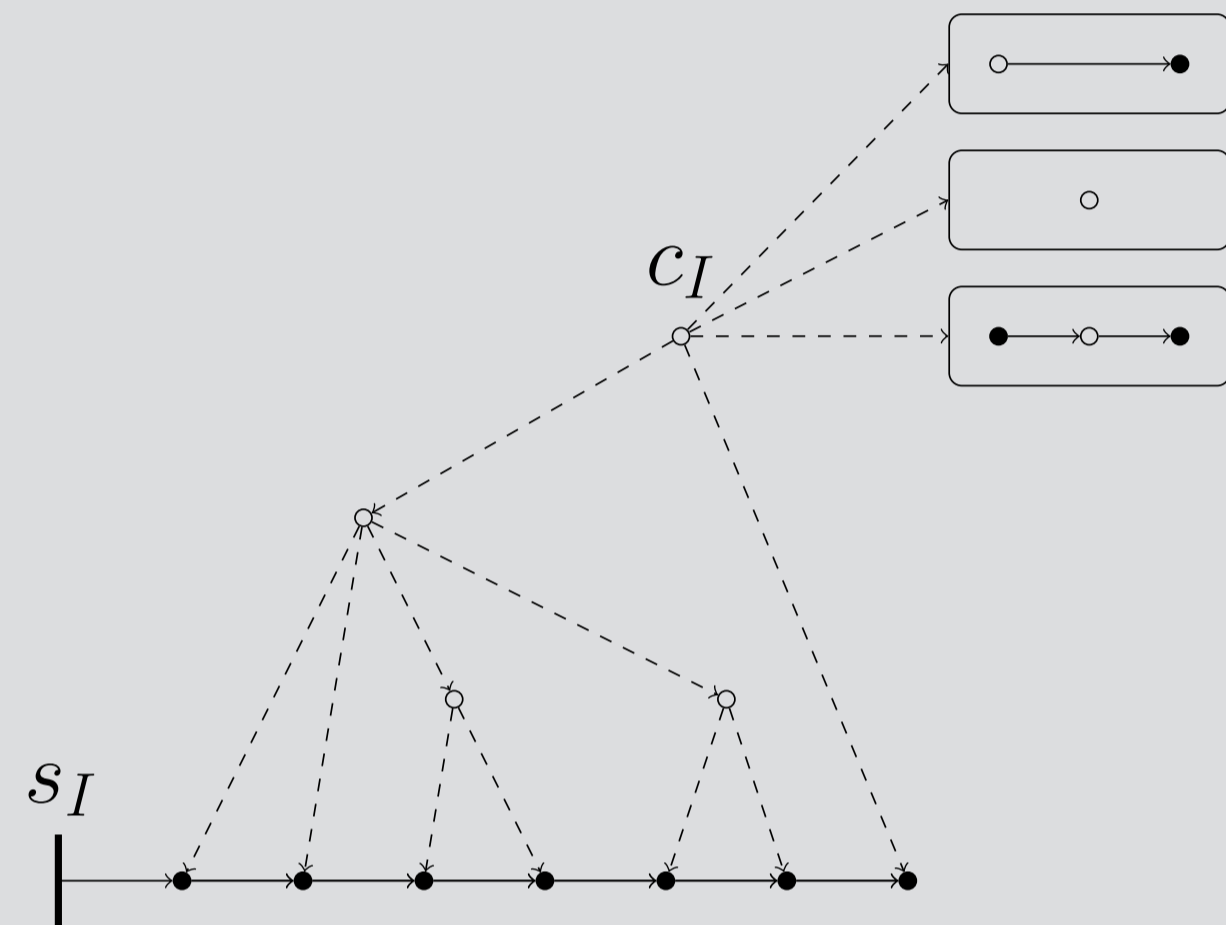
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Motivation

HTN Planning has strong similarities with Formal Grammars. Can we exploit this?

HTN Planning

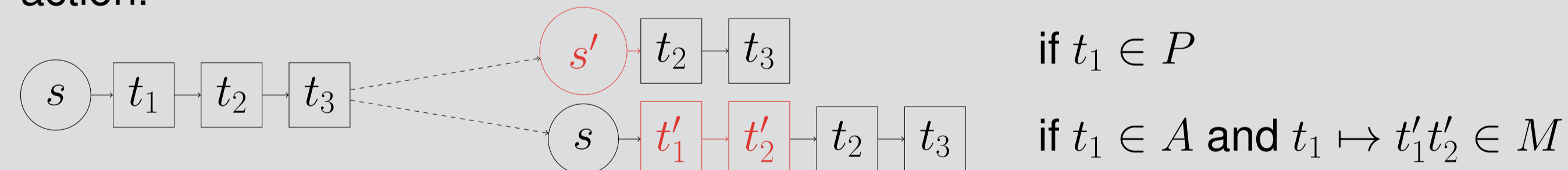


- ▶ Abstract tasks A (\approx non-terminals)
- ▶ Primitive actions P (\approx terminals)
- ▶ Decomposition methods M (\approx refinement rules)
- ▶ Preconditions / Effects for actions
- ▶ Initial state s_I and initial task c_I

Objective: Find a refinement $\pi = \langle p_1, \dots, p_n \rangle$ of c_I containing **only** primitive actions that is **executable** in s_I .

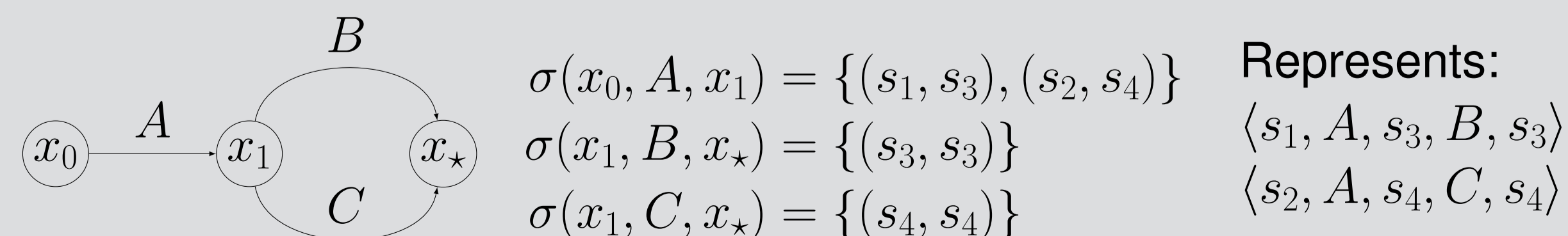
Progression

Search for a plan by applying methods to the **first** task or by applying the **first** action.

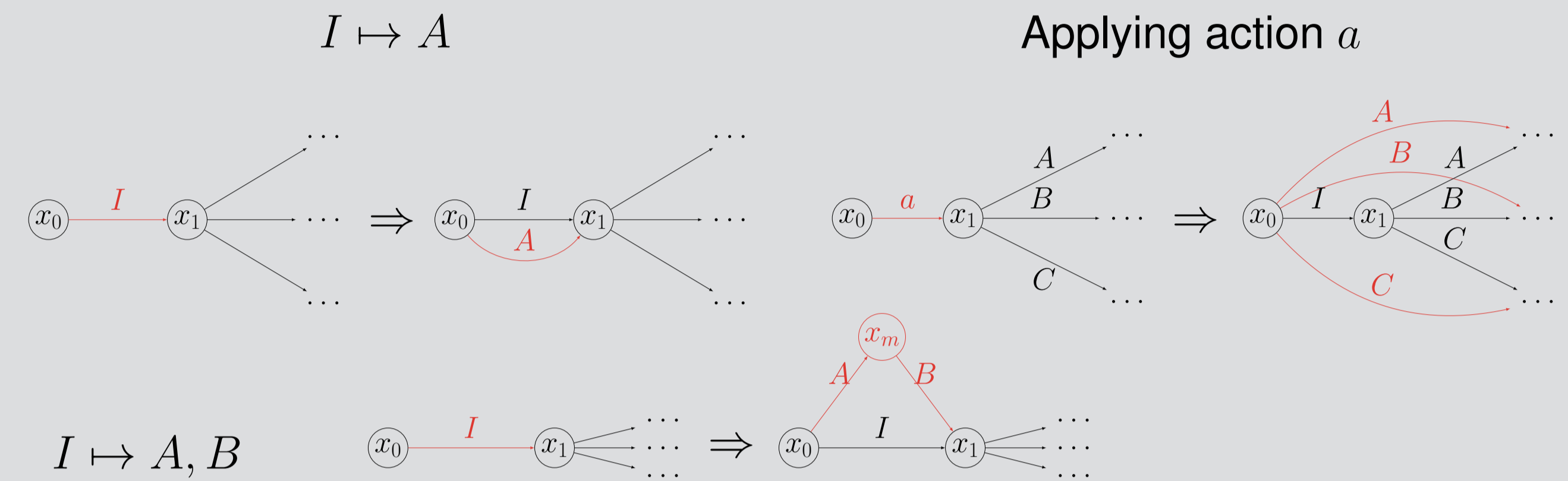


Symbolic Planning

Idea: Use an automaton to represent Progression Search Nodes. Label the edges with BDDs to represent the state.



Performing Progression



Optimal Planning

Given $c : P \mapsto \mathbb{N}_0$, find a plan $\pi = \langle p_1, \dots, p_n \rangle$ with minimal $\sum_{i=1}^n c(p_i)$.

Idea: Construct not one automaton, but one per cost c – the total cost of actions that have already been progressed.

Experiments

Domain (# Inst.)	BDD	SAT(bin)	SAT(dec)	LM-cut A*	TDG-c A*
Barman (20)	0	12	7	0	0
Blocksworld-GTOHP (20)	12	1	1	18	4
Blocksworld-HPDDL (20)	3	3	3	1	0
Childsnack (20)	2	6	6	0	0
Depots (20)	20	10	10	15	3
Entertainment (12)	12	10	12	5	5
Gripper (20)	20	20	20	17	4
Hiking (20)	7	0	0	0	0
Minecraft-Area (30)	15	0	0	0	0
Minecraft-Normal (30)	19	1	0	0	0
Multiarm-Blocksworld (74)	10	0	0	4	0
Robot (10)	1	1	1	0	0
Rover-GTOHP (20)	7	4	4	5	4
Rover-PANDA (20)	13	18	15	10	4
Satellite-GTOHP (20)	3	3	3	5	3
Satellite-PANDA (25)	25	25	25	25	22
SmartPhone (7)	6	7	7	5	4
Towers (14)	10	6	6	9	2
Transport (30)	24	14	12	5	2
UM-Translog (22)	22	22	22	22	22
Woodworking (11)	11	11	11	11	8
Overall (465)	242	174	165	157	87

