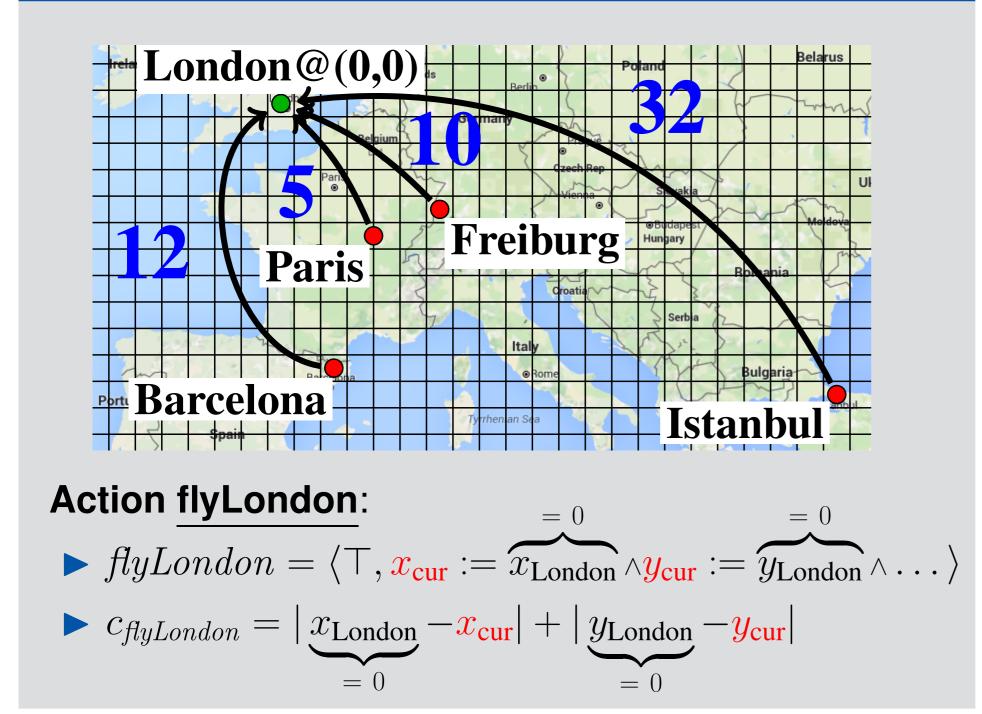
Symbolic Planning with EVMDDs David Speck, Florian Geißer and Robert Mattmüller

University of Freiburg

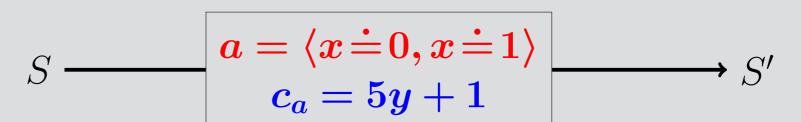
State-Dependent Action Costs (SDAC)

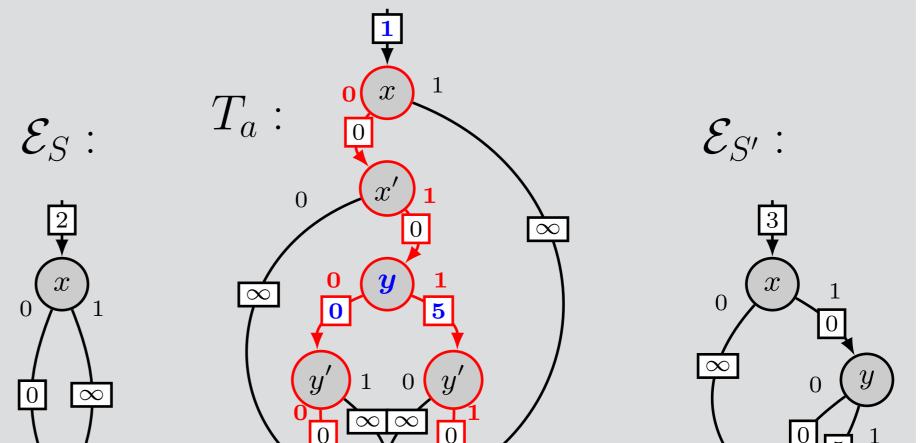
Classical Planning with state dependent costs \triangleright $c_a : S \to \mathbb{N}$ is the *cost function* of action *a*

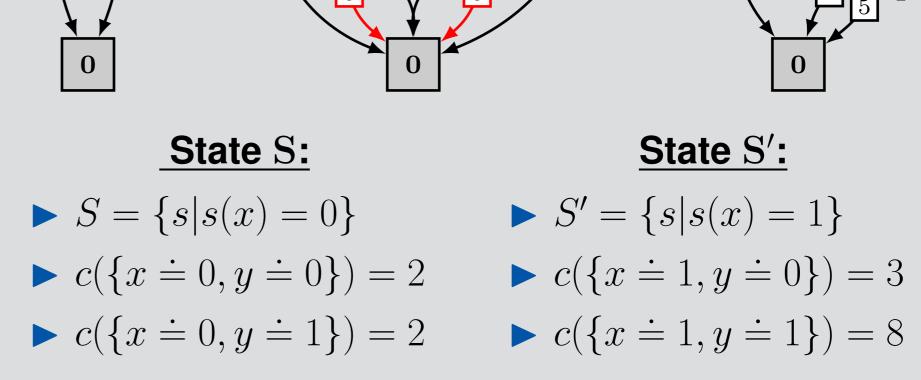
Travelling Salesman Problem



States and Actions







Symbolic Planning

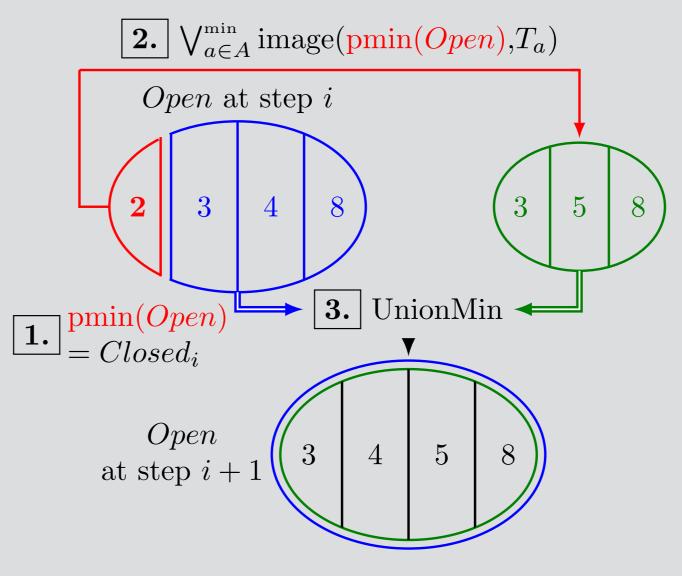
- \blacktriangleright Operations on sets of states $S \subseteq S$
- \triangleright $S \subseteq S$ represented by *characteristic function* χ_S
- ► Manipulating $S \cong$ Transforming χ_S
 - ▶ e.g. $S \cap S' \triangleq \chi_S \land \chi_{S'}$
- Actions represented by transition relations

Edge-Valued Multi-Valued Decision Diagrams (EVMDDs)

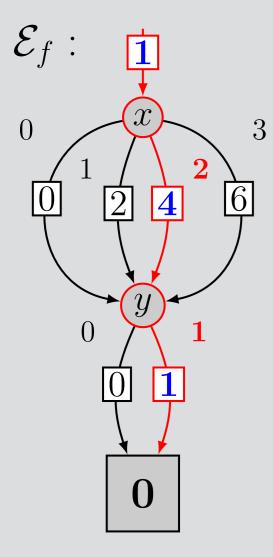
A possible symbolic representation of state sets and transition relations are EVMDDs

General:

EVMDD-A*



1. Extract states with minimal costs



$\triangleright \ \mathcal{S} \to \mathbb{N} \cup \{\infty\}$ Directed acyclic graph Example EVMDD \mathcal{E}_f : ► f(x, y) = 2x + y + 1 $\triangleright \mathcal{D}_x = \{0, 1, 2, 3\}$ $\triangleright \mathcal{D}_y = \{0, 1\}$ \blacktriangleright Evaluation (x = 2 & y = 1) : ► $f(\mathbf{2}, \mathbf{1}) = \mathbf{1} + \mathbf{4} + \mathbf{1} = \mathbf{6}$

Idea:

- Encode cost and reachability with one EVMDD
- \blacktriangleright Unreachable states are mapped to ∞ (cost)

2. Generate successor states with costs

3. Update open list

Experiments + Conclusion

IPC 2014	A^{\star}_{blin}	A [*] Imcut	SYMBA S	YMPLE
Cov.(256)	67	7 86	153	90
SDAC	A^{\star}_{blind}	Sүмва-ехр	SYMBA-cost	SYMPLE

- SYMPLE performs bidirectional EVMDD-A*
- Outperforms other approaches regarding SDAC