

Lecture #9: Control knowledge in planning

What information is provided by heuristic in state-space planning?

Why isn't heuristic $\Delta_0(s,g)$ admissible?

Prove that A* algorithm (tree search) with admissible heuristic is optimal.

What is a serialization of AND/OR graph?

What is the difference between modal operators always and eventually?

How can you describe that p will be true in the third state after the current state?

How do you describe that p will be true in next three states?

How do you describe that there will be a transition between some states s_i and s_{i+1} , where p is true in s_i and not true in s_{i+1} ?

What is progression of the formula? Show how do you progress formulas from previous questions.

How are control rules used in planning?

What is a method in HTN planning?

How is goal defined in HTN planning?

Where is search happening in HTN planning?