Search procedures differ in the way they determine the next node to expand.

**Uninformed Search:** Rigid procedure with no knowledge of the cost of a given node to the goal.

**Informed Search:** Knowledge of the worth of expanding a node $n$ is given in the form of an evaluation function $f(n)$, which assigns a real number to each node. Mostly, $f(n)$ includes as a component a heuristic function $h(n)$, which estimates the costs of the cheapest path from $n$ to the goal.

**Best-First Search:** Informed search procedure that expands the node with the “best” $f$-value first.
function TREE-SEARCH(problem) returns a solution, or failure
    initialize the frontier using the initial state of problem
    loop do
        if the frontier is empty then return failure
        choose a leaf node and remove it from the frontier
        if the node contains a goal state then return the corresponding solution
        expand the chosen node, adding the resulting nodes to the frontier

Best-first search is an instance of the general TREE-SEARCH algorithm in which frontier is a priority queue ordered by an evaluation function $f$.

When $f$ is always correct, we do not need to search!
A possible way to judge the “worth” of a node is to estimate its path-costs to the goal.

\[ h(n) = \text{estimated path-costs from } n \text{ to the goal} \]

The only real restriction is that \( h(n) = 0 \) if \( n \) is a goal.

A best-first search using \( h(n) \) as the evaluation function, i.e., \( f(n) = h(n) \) is called a greedy search.

Example: route-finding problem:
\( h(n) = \text{straight-line distance from } n \text{ to the goal} \)
The evaluation function $h$ in greedy searches is also called a *heuristic* function or simply a *heuristic*.

- The word *heuristic* is derived from the Greek word $\varepsilon\upsilon\rho\iota\sigma\kappa\varepsilon\iota\nu$ (note also: $\varepsilon\upsilon\rho\eta\kappa\alpha$!)

- The mathematician Polya introduced the word in the context of problem solving techniques.

- In AI it has two meanings:
  - Heuristics are fast but in certain situations incomplete methods for problem-solving [Newell, Shaw, Simon 1963] (The greedy search is actually generally incomplete).
  - Heuristics are methods that improve the search in the average-case.

→ In all cases, the heuristic is *problem-specific and focuses* the search!
Greedy Search Example

[Diagram showing a network of cities with distances between them]

Arad 366
Bucharest 0
Craiova 160
Drobeta 242
Eforie 161
Fagaras 176
Giurgiu 77
Hirsova 151
Iasi 226
Lugoj 244
Mehadia 241
Neamt 234
Oradea 380
Pitesti 100
Rimnicu Vilcea 193
Sibiu 253
Timisoara 329
Vaslui 199
Zerind 374
Greedy Search from Arad to Bucharest

(a) The initial state

(b) After expanding Arad

(c) After expanding Sibiu

(d) After expanding Fagaras
Greedy Search - Properties

- a good heuristic might reduce search time drastically
- non-optimal
- incomplete
- graph-search version is complete only in finite spaces

Can we do better?
A*: Minimization of the Estimated Path Costs

A* combines greedy search with the uniform-cost search:
Always expand node with lowest \( f(n) \) first, where

\[
\begin{align*}
g(n) & = \text{actual cost from the initial state to } n, \\
\ h(n) & = \text{estimated cost from } n \text{ to the nearest goal.} \\
\ f(n) & = g(n) + h(n), \\
& \text{the estimated cost of the cheapest solution through } n.
\end{align*}
\]

Let \( h^*(n) \) be the actual cost of the optimal path from \( n \) to the nearest goal. \( h \) is admissible if the following holds for all \( n \):

\[
h(n) \leq h^*(n)
\]

We require that for A*, \( h \) is admissible (example: straight-line distance is admissible).
In other words, \( h \) is an optimistic estimate of the costs that actually occur.
A* Search Example

(University of Freiburg)
A* Search from Arad to Bucharest

(a) The initial state

(b) After expanding Arad

(c) After expanding Sibiu

(d) After expanding Rimnicu Vilcea

(University of Freiburg) Foundations of AI May 2, 2018 12 / 32
A* Search from Arad to Bucharest

(e) After expanding Fagaras

(f) After expanding Pitesti
Example: Path Planning for Robots in a Grid-World

Live-Demo: http://qiao.github.io/PathFinding.js/visual/
**Optimality of A**

**Claim:** The first solution found (= node is expanded and found to be a goal node) has the minimum path cost.

**Proof:** Suppose there exists a goal node $G$ with optimal path cost $f^*$, but $A^*$ has found another node $G_2$ with $g(G_2) > f^*$. 

![Diagram](https://via.placeholder.com/150)
Let $n$ be a node on the path from the start to $G$ that has not yet been expanded. Since $h$ is admissible, we have

$$f(n) \leq f^*.$$ 

Since $n$ was not expanded before $G_2$, the following must hold:

$$f(G_2) \leq f(n)$$

and

$$f(G_2) \leq f^*.$$ 

It follows from $h(G_2) = 0$ that

$$g(G_2) \leq f^*.$$ 

$\rightarrow$ Contradicts the assumption!
Completeness and Complexity

**Completeness:**
If a solution exists, A* will find it provided that (1) every node has a finite number of successor nodes, and (2) there exists a positive constant $\delta > 0$ such that every step has at least cost $\delta$.

$\rightarrow$ there exists only a finite number of nodes $n$ with $f(n) \leq f^*$.

**Complexity:**
In general, still exponential in the path length of the solution (space, time)

More refined complexity results depend on the assumptions made, e.g. on the quality of the heuristic function. Example:

In the case in which $|h^*(n) - h(n)| \leq O(\log(h^*(n)))$, only one goal state exists, and the search graph is a tree, a sub-exponential number of nodes will be expanded [Gaschnig, 1977, Helmert & Roeger, 2008]. Unfortunately, this almost never holds.
A note on Graph- vs. Tree-Search

- A* as described is a tree-search (and may consider duplicates)
- For the graph-based variant, one
  - either needs to consider re-opening nodes from the explored set, when a better estimate becomes known, or
  - one needs to require stronger restrictions on the heuristic estimate: it needs to be consistent.

→ A heuristic $h$ is called **consistent** iff for all actions $a$ leading from $s$ to $s'$: $h(s) - h(s') \leq c(a)$, where $c(a)$ denotes the cost of action $a$.

- **Note**: Consistency implies admissibility.
Heuristic Function Example

\[ h_1 = \text{the number of tiles in the wrong position} \]
\[ h_2 = \text{the sum of the distances of the tiles from their goal positions (Manhattan distance)} \]
Empirical Evaluation

- $d = \text{distance from goal}$
- Average over 100 instances

<table>
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<tr>
<th>$d$</th>
<th>IDS</th>
<th>$A^*(h_1)$</th>
<th>$A^*(h_2)$</th>
<th>IDS</th>
<th>$A^*(h_1)$</th>
<th>$A^*(h_2)$</th>
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<td>39135</td>
<td>1641</td>
<td>-</td>
<td>1.48</td>
<td>1.26</td>
</tr>
</tbody>
</table>
A* in general still suffers from exponential memory growth. Therefore, several refinements have been suggested:

- iterative-deepening A*, where the f-costs are used to define the cutoff (rather than the depth of the search tree): IDA*

- Recursive Best First Search (RBFS): introduces a variable \( f_{\text{limit}} \) to keep track of the best alternative path available from any ancestor of the current node. If current node exceeds this limit, recursion unwinds back to the alternative path.

- other alternatives memory-bounded A* (MA*) and simplified MA* (SMA*).
Local Search Methods

- In many problems, it is unimportant how the goal is reached—only the goal itself matters (8-queens problem, VLSI Layout, TSP).
- If in addition a quality measure for states is given, **local search** can be used to find solutions.
- It operates using a single current node (rather than multiple paths).
- It requires little memory.
- **Idea:** Begin with a randomly-chosen configuration and improve on it step by step → **Hill Climbing**.
- **Note:** It can be used for maximization or minimization respectively (see 8-queens example)
Example state with heuristic cost estimate $h = 17$ (counts the number of pairs threatening each other directly or indirectly).
function HILL-CLIMBING(problem) returns a state that is a local maximum

current ← MAKE-NODE(problem.INITIAL-STATE)

loop do
    neighbor ← a highest-valued successor of current
    if neighbor.VALUE ≤ current.VALUE then return current.STATE
    current ← neighbor
Possible realization of a hill-climbing algorithm:
Select a column and move the queen to the square with the fewest conflicts.
Problems with Local Search Methods

- **Local maxima:** The algorithm finds a sub-optimal solution.
- **Plateaus:** Here, the algorithm can only explore at random.
- Ridges: Similar to plateaus but might even require suboptimal moves.

**Solutions:**

- **Start over** when no progress is being made.
- “Inject noise” → random walk

Which strategies (with which parameters) are successful (within a problem class) can usually only empirically be determined.
Local minimum \((h = 1)\) of the 8-queens Problem. Every successor has a higher cost.
Illustration of the ridge problem

The grid of states (dark circles) is superimposed on a ridge rising from left to right, creating a sequence of local maxima, that are not directly connected to each other. From each local maximum, all the available actions point downhill.
The 8-queens problem has about $8^8 \approx 17$ million states. Starting from a random initialization, hill-climbing directly finds a solution in about 14% of the cases. On average it requires only 4 steps!

Better algorithm: Allow sideways moves (no improvement), but restrict the number of moves (avoid infinite loops!).

E.g.: max. 100 moves: Solves 94%, number of steps raises to 21 steps for successful instances and 64 for failure cases.
Simulated Annealing

In the simulated annealing algorithm, “noise” is injected systematically: first a lot, then gradually less.

```plaintext
function SIMULATED-ANNEALING(problem, schedule) returns a solution state
inputs: problem, a problem
         schedule, a mapping from time to “temperature”

current ← MAKE-NODE(problem.INITIAL-STATE)
for t = 1 to ∞ do
    T ← schedule(t)
    if T = 0 then return current
    next ← a randomly selected successor of current
    ΔE ← next.VALUE - current.VALUE
    if ΔE > 0 then current ← next
    else current ← next only with probability e^{ΔE/T}
```

Has been used since the early 80’s for VSLI layout and other optimization problems.
Evolution appears to be very successful at finding good solutions.

**Idea:** Similar to evolution, we search for solutions by three operators: “mutation”, “crossover”, and “selection”.

**Ingredients:**
- Coding of a solution into a string of symbols or bit-string
- A fitness function to judge the worth of configurations
- A population of configurations

**Example:** 8-queens problem as a chain of eight numbers. Fitness is judged by the number of non-attacks. The population consists of a set of arrangements of queens.
Selection, Mutation, and Crossing

Many variations:
how selection will be applied, what type of cross-over operators will be used, etc.

Selection of individuals according to a fitness function and pairing

Calculation of the breaking points and recombination

According to a given probability elements in the string are modified.
Heuristics focus the search

Best-first search expands the node with the highest worth (defined by any measure) first.

With the minimization of the evaluated costs to the goal $h$ we obtain a greedy search.

The minimization of $f(n) = g(n) + h(n)$ combines uniform and greedy searches. When $h(n)$ is admissible, i.e., $h^*$ is never overestimated, we obtain the A* search, which is complete and optimal.

IDA* is a combination of the iterative-deepening and A* searches.

Local search methods only ever work on one state, attempting to improve it step-wise.

Genetic algorithms imitate evolution by combining good solutions.