

Discovering Generalized Landmarks:

Patterns in Abstract States of Real-World Problems

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PROBLEM

- **AI Planning: Traditional landmarks (atoms)**
- **Limitations**
 - Recomputed for every instance
 - Disjunctive landmarks
 - Problem symmetries

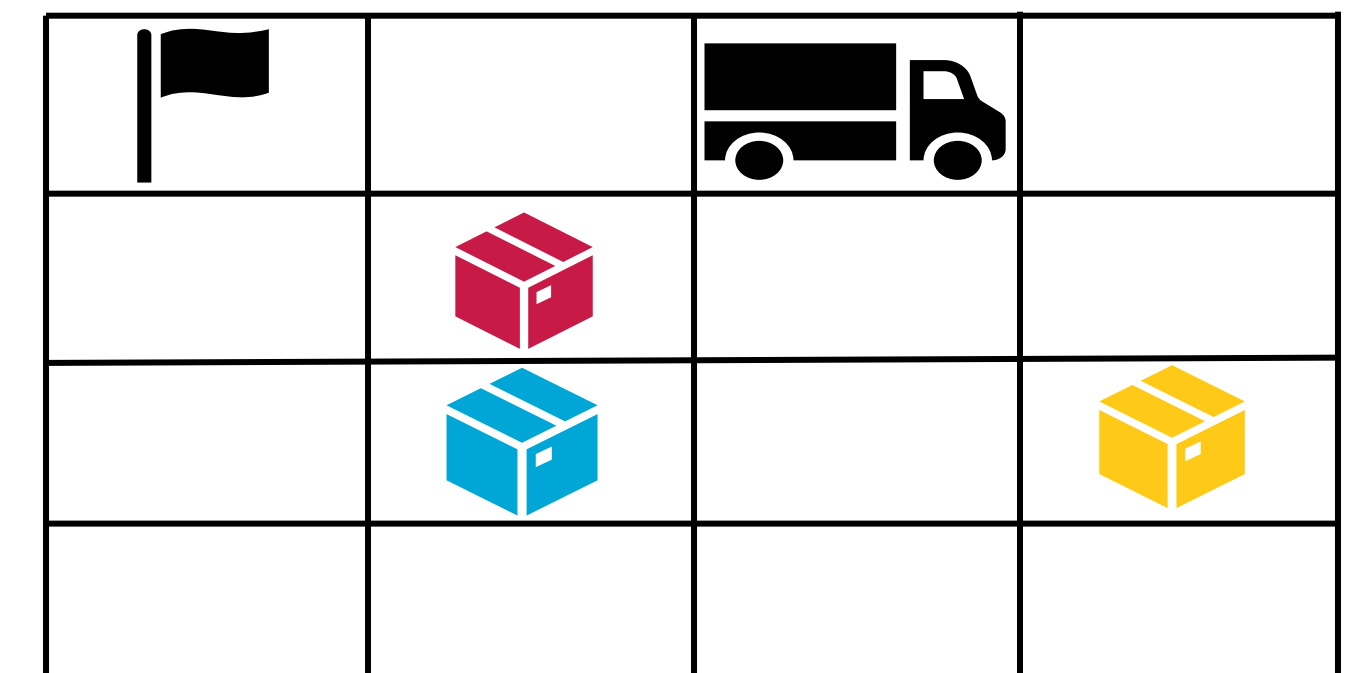
Example: Delivery problem

Predicates:

- at(Object,Cell)
- carrying(Truck,Package)
- empty(Truck)
- adjacent(Cell1,Cell2)

Actions:

- pick-package(Truck,Package,Cell)
- drop-package(Truck,Package,Cell)
- move(Truck,Cell1,Cell2)



Traditional landmarks:

- at(truck1,cell-1-1)
- carrying(truck1,packageRed)

LANDMARKS

Generalized landmarks

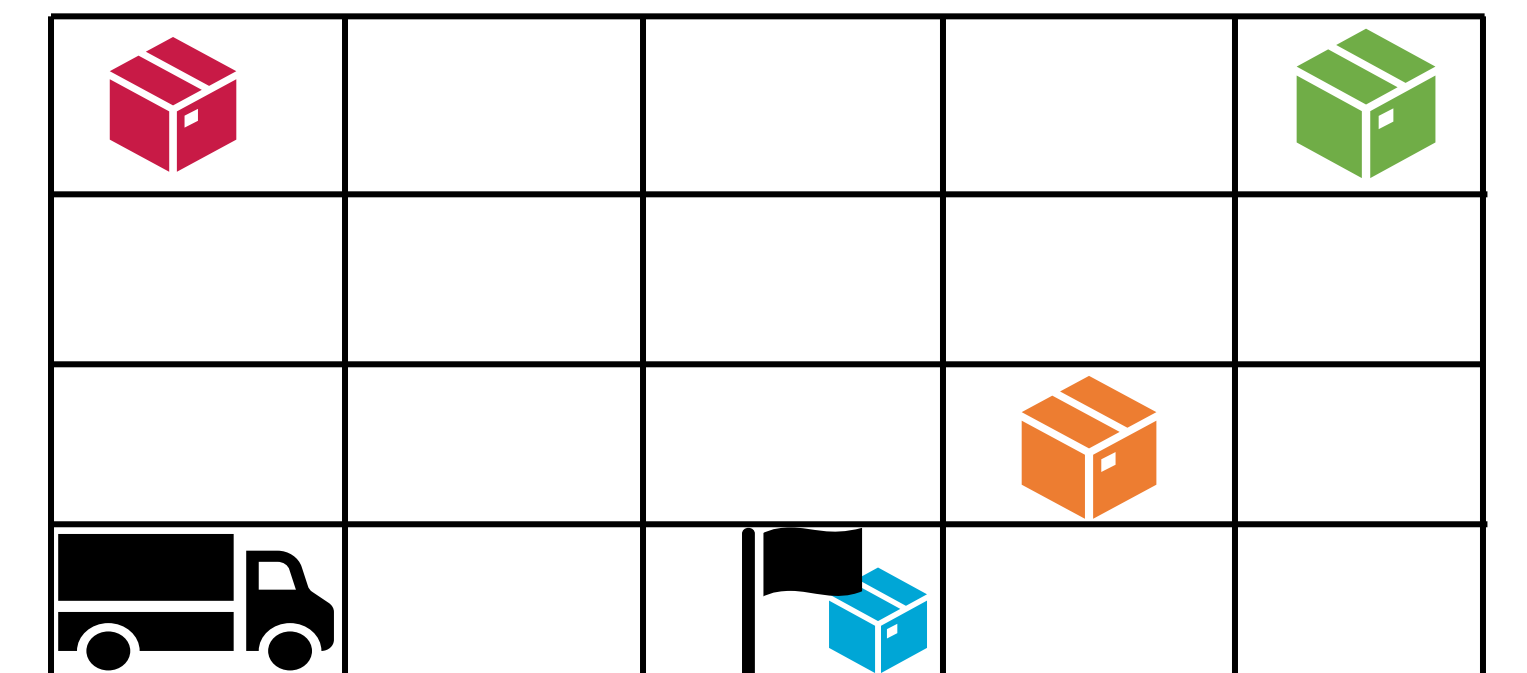
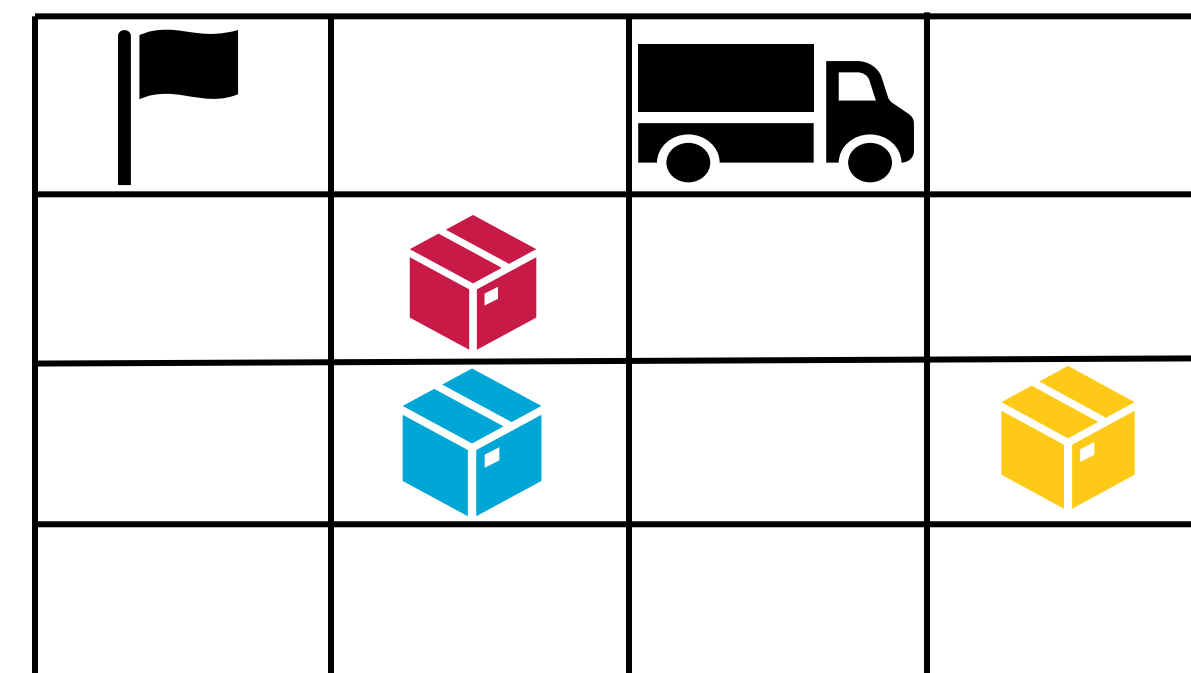
- Landmark is a formula over features as state indicator
- Generalize across instance
- Generalize across objects
- Graph with ordered landmarks
- Conditional looped edges

Traditional: at(truck1, cell-1-1)

Generalized: truck at a cell with a package

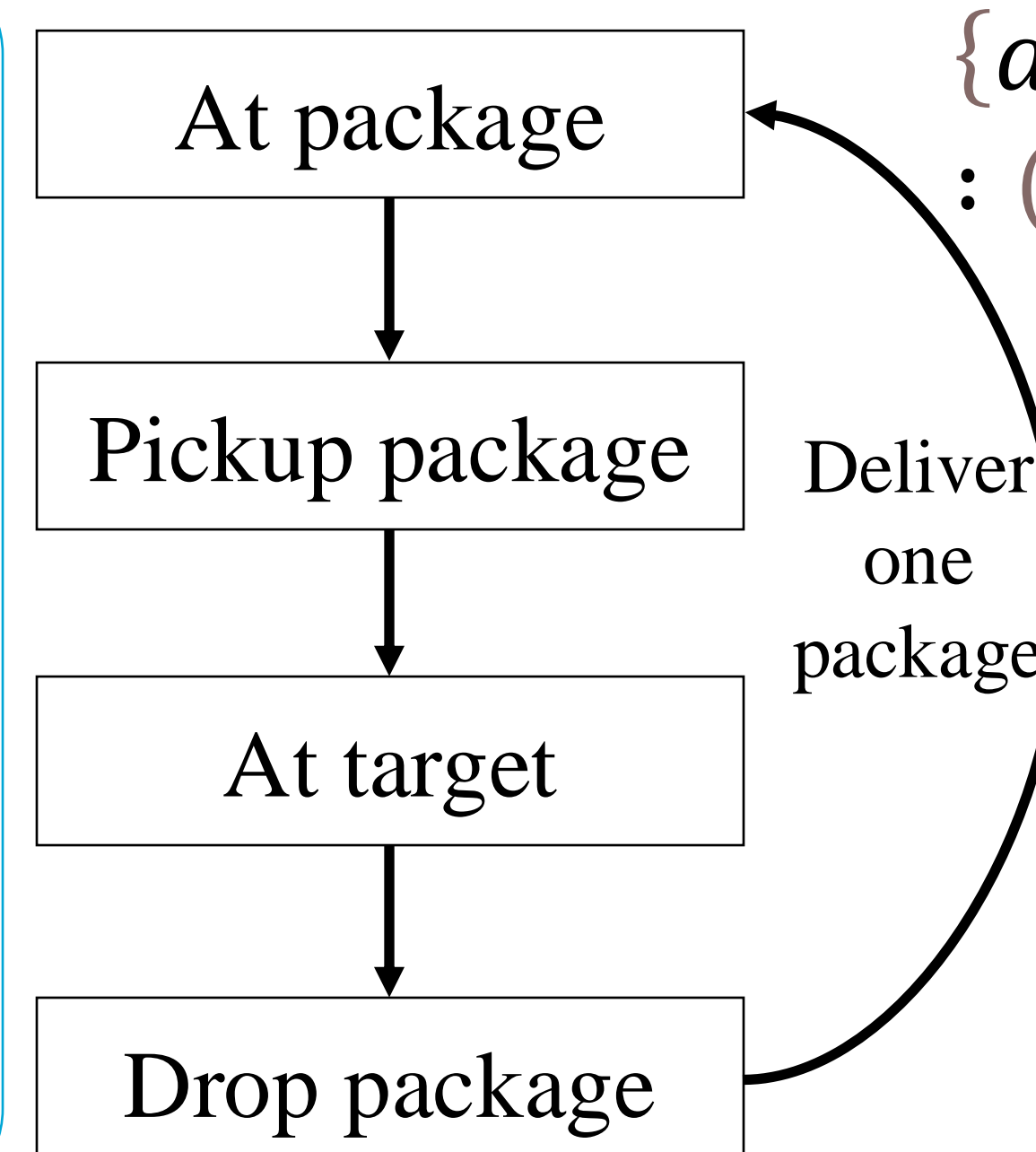
Traditional: carrying(truck1, package1) → at(package1, c-0-0)

Generalized: carrying a package and not at a goal cell → at a goal cell



DISCOVERY

1. Find set of training plans
 - Create state trajectories
2. Generate features and filter to useful ones
3. Feature valuations in all training states
4. Extract set of feature for next landmark
5. Detect loops to previous landmarks
6. Create graph



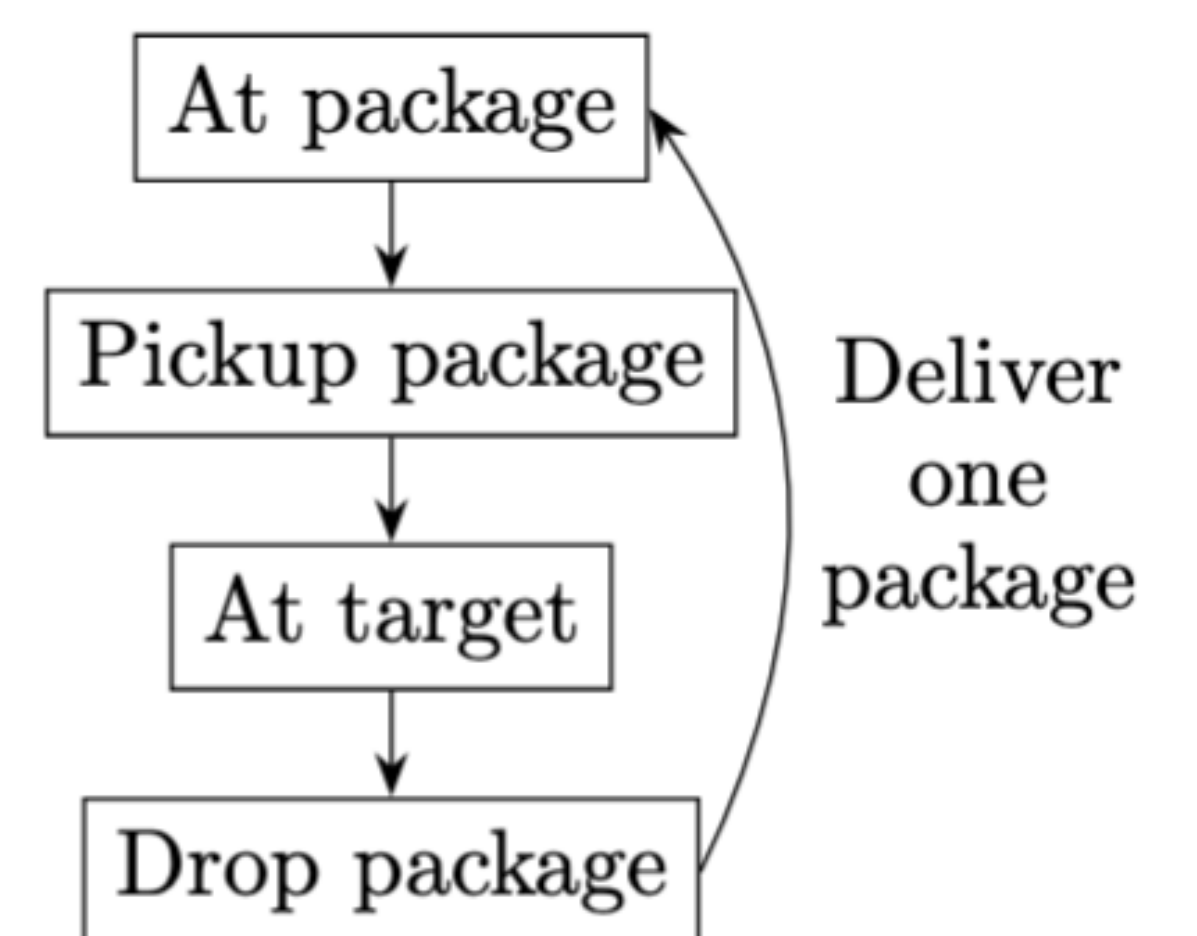
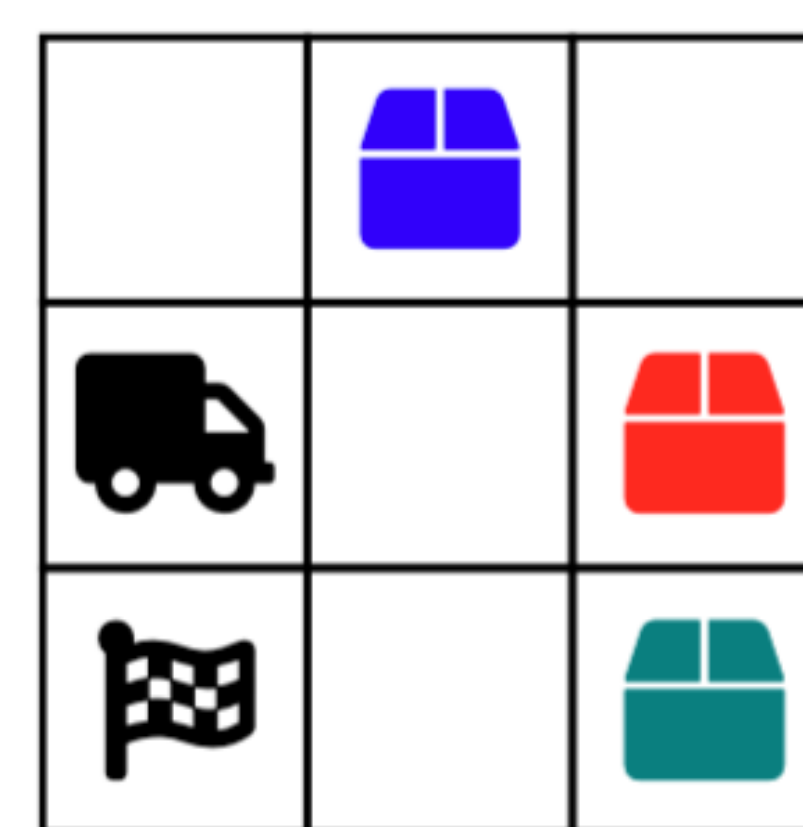
$$\{a \mid \exists b : (a, b) \in [at(a, b)] \cap b \in \{c \mid \forall d : (c, d) \in [at(d, c)] \rightarrow e \in [truck(e)]\}\}$$

Truck is empty and there is a package at this cell

$$n_count(c_some(r_primitive(at_g, 0, 1), c_some(r_inverse(r_primitive(at, 0, 1)), c_primitive(truck, 0))))$$

ISLAND PLANNING

- Plan between landmarks
- Update state
- Check for loops
- Planner independent
 - Example ASP: increasing horizon
- Next: Railway application
 - Park train 1 at a different track than train 2



(a) Instance with 3 packages. (b) Generalized landmarks.

