

# Uninformed Search

## Chapter 3

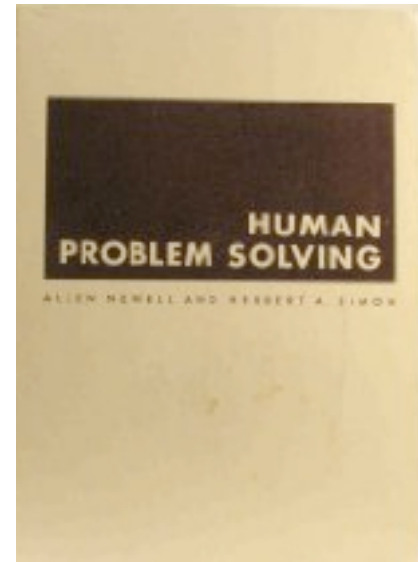
Some material adopted from notes  
by Charles R. Dyer, University of  
Wisconsin-Madison

# Today's topics

- Goal-based agents
- Representing states and actions
- Example problems
- Generic state-space search algorithm
- Specific algorithms
  - Breadth-first search
  - Depth-first search
  - Uniform cost search
  - Depth-first iterative deepening
- Example problems revisited

# Big Idea

[Allen Newell](#) and [Herb Simon](#) developed the *problem space principle* as an AI approach in the late 60s/early 70s



"The rational activity in which people engage to solve a problem can be described in terms of (1) a set of **states** of knowledge, (2) **operators** for changing one state into another, (3) **constraints** on applying operators and (4) **control** knowledge for deciding which operator to apply next."

*Newell A & Simon H A. Human problem solving.*  
Englewood Cliffs, NJ: Prentice-Hall. 1972.

# Example: 8-Puzzle

Given an initial configuration of 8 numbered tiles on a 3x3 board, move the tiles to produce a desired goal configuration

5	4	
6	1	8
7	3	2

Start State

1	2	3
8		4
7	6	5

Goal State

# 15 puzzle

- Popularized, but not invented, by [Sam Loyd](#)
- He [offered](#) \$1000 to all who could solve it in 1896
- He sold many puzzles
- Its states form two *disjoint* spaces
- There was no path to solution from initial state!

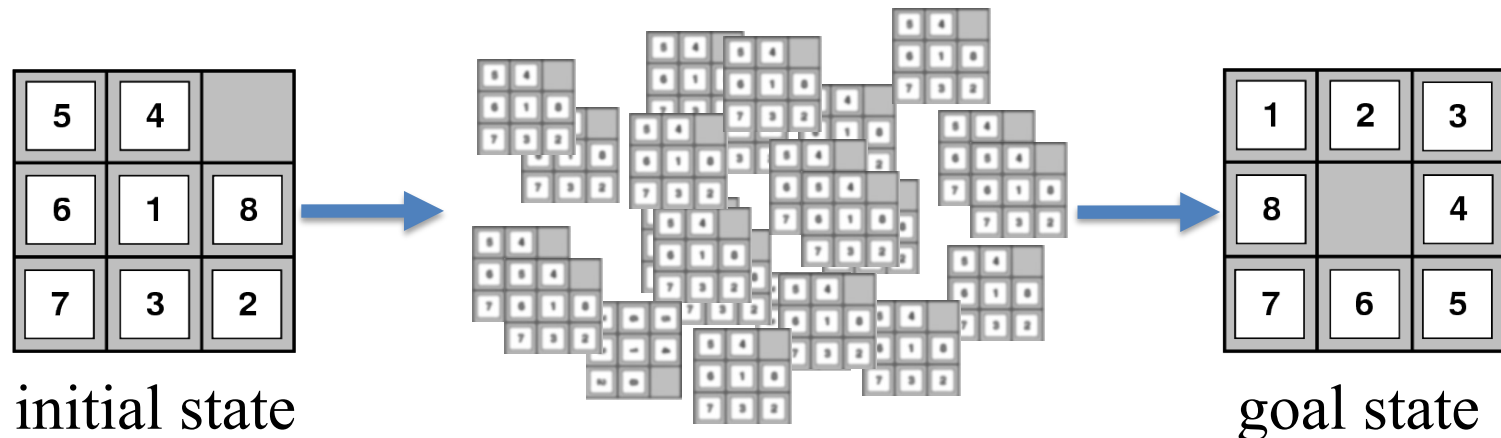


Sam Loyd's 1914 illustration of the unsolvable variation

# Building goal-based agents

We must answer the following questions

- How do we represent the **state** of the “world”?
- What is the **goal** and how can we recognize it?
- What are the possible **actions**?
- What *relevant* information do we encoded to describe states, actions and their effects and thereby solve the problem?



# Representing states

- State of an 8-puzzle?

5	4	
6	1	8
7	3	2

# Representing states

5	4	
6	1	8
7	3	2

- State of an 8-puzzle?
- A 3x3 array of integer in {0..8}
- No integer appears twice
- 0 represents the empty space
  
- In Python, we might implement this using a nine-character string: "540681732"
- And write functions to map the 2D coordinates to an index



# What's the goal to be achieved?



- Describe situation we want to achieve, a set of properties that we want to hold, etc.
- Defining a **goal test** function that when applied to a state returns True or False
- For our problem:

```
def isGoal(state):  
    return state == "123405678"
```

# What are the actions?



- **Primitive actions** for changing the state
  - In a **deterministic** world: no uncertainty in an action's effects (simple model)
- Given action and description of **current world state**, action completely specifies
  - Whether action **can** be applied to the current world (i.e., is it applicable and legal?) and
  - What state **results** after action is performed in the current world (i.e., no need for *history* information to compute the next state)

# Representing actions



- Actions ideally considered as **discrete events** that occur at an **instant of time**
- Example, in a planning context
  - If `state:inClass` and perform `action:goHome`, then next state is `state:atHome`
  - There's no time where you're neither in class nor at home (i.e., in the state of “going home”)

# Representing actions

- Actions for 8-puzzle?

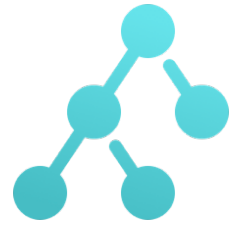
5	4	
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# Representing actions

5	4	
6	1	8
7	3	2

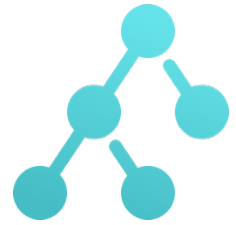
- Actions for 8-puzzle?
- Number of actions/operators depends on the **representation** used in describing a state
  - Specify 4 possible moves for each of the 8 tiles, resulting in a total of  **$4*8=32$  operators**
  - Or, Specify four moves for “blank” square and we only need **4 operators**
- **Representational shift can simplify a problem!**

# Representing states



- **Size of a problem** usually described in terms of possible **number of states**
  - Tic-Tac-Toe has about  $3^9$  states ( $19,683 \approx 2 * 10^4$ )
  - Checkers has about  $10^{40}$  states
  - Rubik's Cube has about  $10^{19}$  states
  - Chess has about  $10^{120}$  states in a typical game
  - Go has  $2 * 10^{170}$
  - Theorem provers may deal with an infinite space
- State space size  $\approx$  solution difficulty

# Representing states



- Our estimates were loose upper bounds
- How many **possible, legal** states does tic-tac-toe really have?
- Simple upper bound: nine board cells, each of which can be empty, O or X, so  $3^9$
- Only 593 states after eliminating

– impossible states 

– Rotations and reflections 

# Some example problems

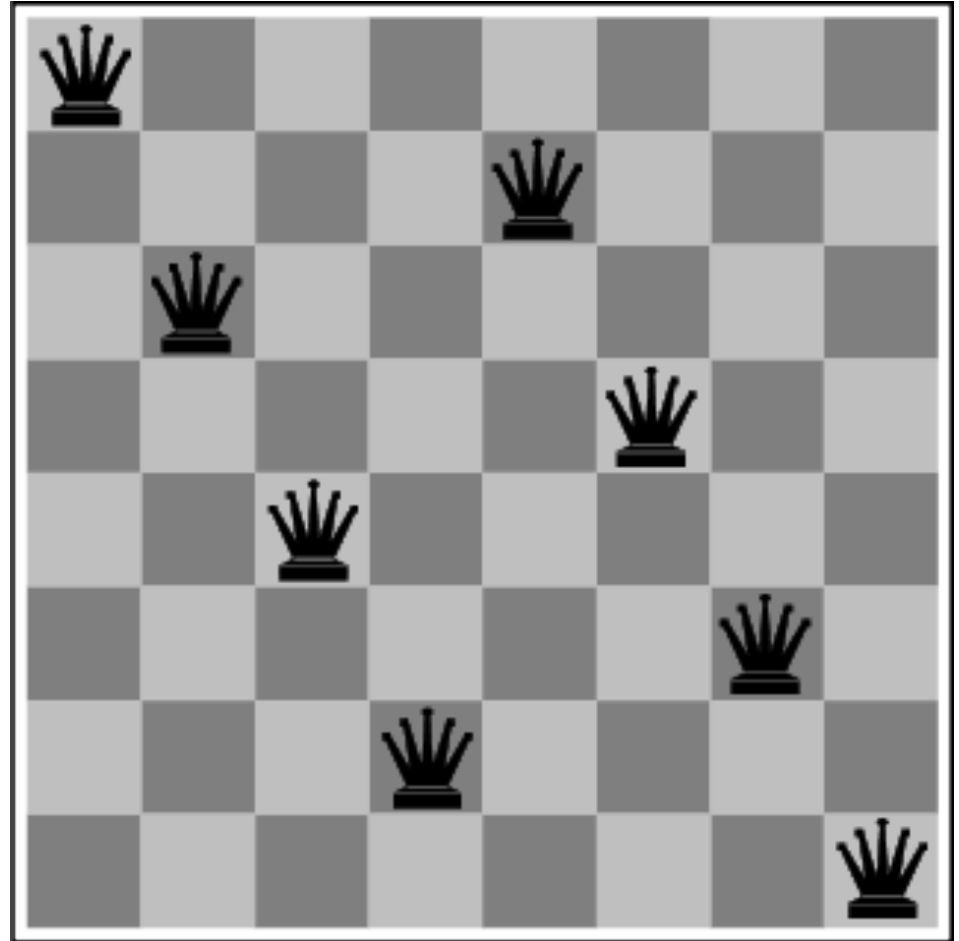
- Toy problems and micro-worlds
  - 8-Puzzle
  - Missionaries and Cannibals
  - Cryptarithmic
  - Remove 5 Sticks
  - Water Jug Problem
- Real-world problems



# The 8-Queens Puzzle

Place eight queens on a chessboard such that no queen attacks any other

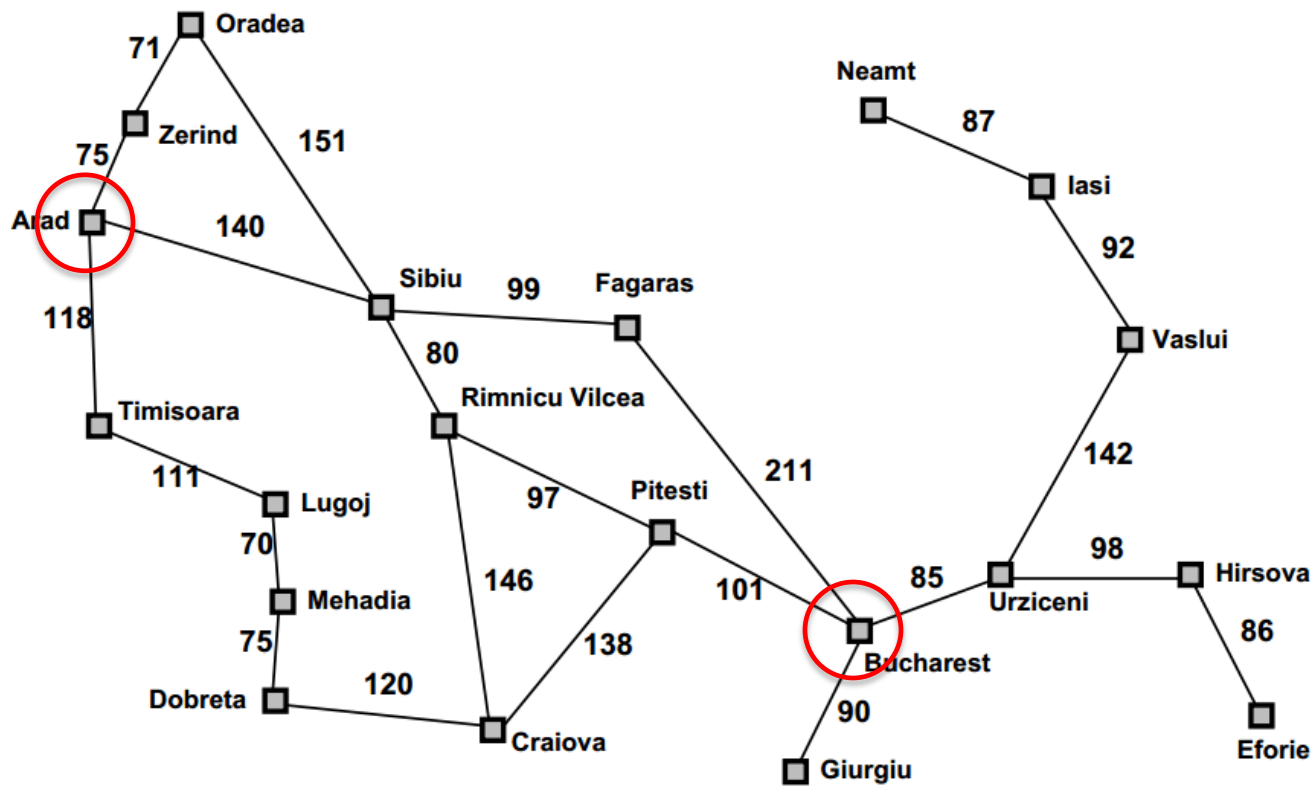
We can generalize the problem to a  $N \times N$  chessboard



*What are the states, goal test, actions?*

# Route Planning

Find a route from Arad to Bucharest



A simplified map of major roads in Romania used in our text

# Water Jug Problem



- Two jugs  $J1$  &  $J2$  with capacity  $C1$  &  $C2$
- Initially  $J1$  has  $W1$  water and  $J2$  has  $W2$  water
  - e.g.: full 5 gallon jug and empty 2 gallon jug
- Possible actions:
  - Pour from jug  $X$  to jug  $Y$  until  $X$  empty or  $Y$  full
  - Empty jug  $X$  onto the floor
- Goal:  $J1$  has  $G1$  water and  $J2$   $G2$ 
  - $G1$  or  $G2$  can be  $-1$  to represent any amount
- E.g.: initially full jugs with capacities 3 and 1 liters, goal is to have 1 liter in each

# So...

- How can we represent the states?
- What an initial state
- How do we recognize a goal state
- What are the actions; how can we tell which ones can be performed in a given state; what is the resulting state
- How do we search for a solution from an initial state given a goal state
- What is a solution? The goal state achieved or a path to it?

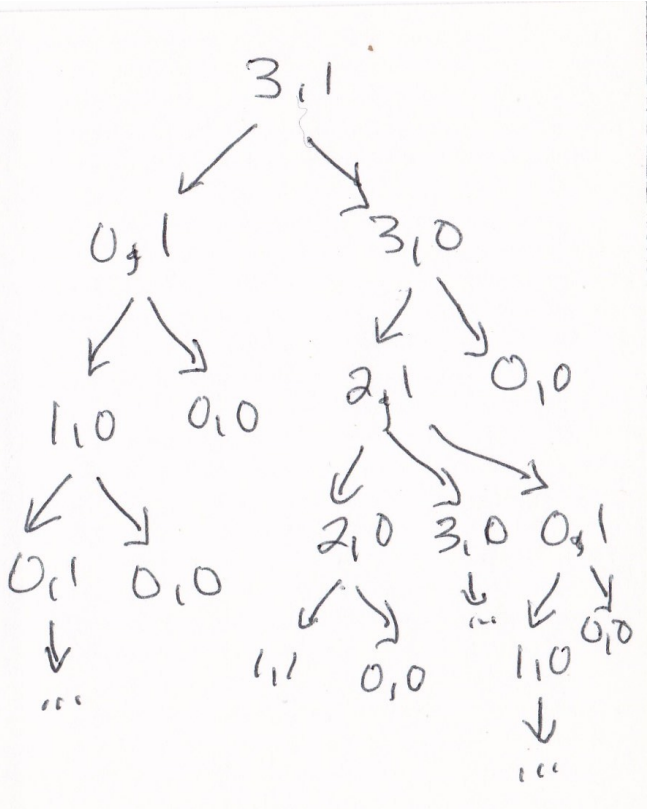
# Search in a state space

- Basic idea:
  - Create representation of initial state
  - Try all possible actions & connect states that result
  - Recursively apply process to the new states until we find a solution or dead ends
- We need to keep track of the connections between states and might use a
  - Tree data structure or
  - Graph data structure
- A graph structure is best in general...

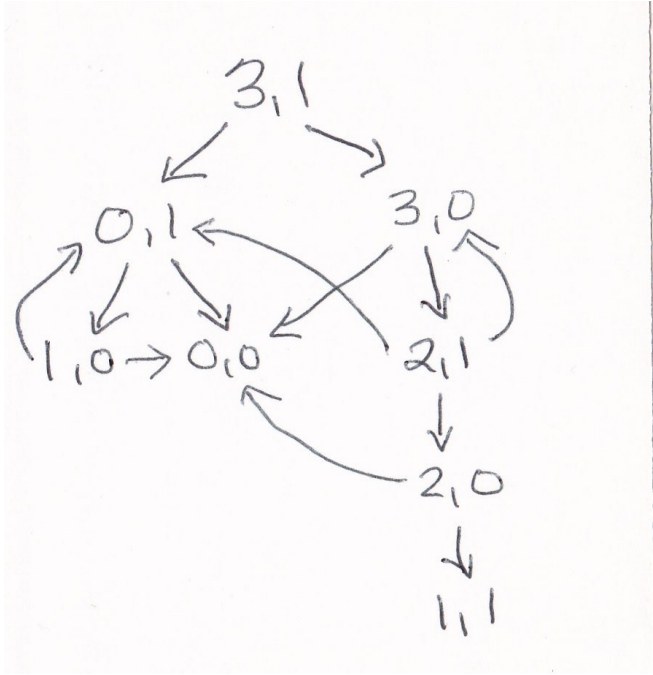
# Search in a state space

Consider a water jug problem with a 3-liter and 1-liter jug, an initial state of (3,1) and a goal stage of (1,1)

**Tree model of space**



**Graph model of space**



graph model avoids redundancy and loops and is usually preferred

# Formalizing state space search

- A state space is a **graph**  $(V, E)$  where  $V$  is a set of **nodes** and  $E$  is a set of **arcs**, and each arc is directed from a node to another node
- **Nodes:** data structures with state description and other info, e.g., node's parent, name of action that generated it from parent, etc.
- **Arcs:** instances of actions, head is a state, tail is the state that results from action

# Formalizing search in a state space

- Each arc has fixed, positive **cost** associated with it corresponding to the action cost
  - Simple case: all costs are 1
- Each node has a set of **successor nodes** corresponding to all legal actions that can be applied at node's state
  - **Expanding** a node = generating its successor nodes and adding them and their associated arcs to the graph
- One or more nodes are marked as **start nodes**
- A **goal test** predicate is applied to a state to determine if its associated node is a goal node



# Example: Water Jug Problem



- Two jugs J1 and J2 with capacity C1 and C2
- Initially J1 has W1 water and J2 has W2 water
  - e.g.: a full 5-gallon jug and an empty 2-gallon jug
- Possible actions:
  - Pour from jug X to jug Y until X empty or Y full
  - Empty jug X onto the floor
- Goal: J1 has G1 water and J2 G2
  - G1 or G0 can be -1 to represent any amount



# Example: Water Jug Problem



Given full 5-gal. jug  
and empty 2-gal. jug,  
fill 2-gal jug with one  
gallon

- State =  $(x,y)$ , where  $x$  is water in jug 1;  $y$  is water in jug 2
- Initial State =  $(5,0)$
- Goal State =  $(-1,1)$ , where -1 means any amount

Action table

Name	Cond.	Transition	Effect
dump1	$x > 0$	$(x,y) \rightarrow (0,y)$	Empty Jug 1
dump2	$y > 0$	$(x,y) \rightarrow (x,0)$	Empty Jug 2
pour_1_2	$x > 0$ & $y < C2$	$(x,y) \rightarrow (x-D,y+D)$ $D = \min(x, C2-y)$	Pour from Jug 1 to Jug 2
pour_2_1	$y > 0$ & $X < C1$	$(x,y) \rightarrow (x+D,y-D)$ $D = \min(y, C1-x)$	Pour from Jug 2 to Jug 1

# Formalizing search

- **Solution:** sequence of actions associated with a path from a start node to a goal node
- **Solution cost:** sum of the arc costs on the solution path
  - If all arcs have same (unit) cost, then solution cost is length of solution (number of steps)
  - Algorithms generally require that arc costs cannot be negative (why?)

# Formalizing search

- **State-space search:** searching through state space for solution by **making explicit** a portion of an **implicit** state-space graph to find a goal node
  - Can't materializing whole space for large problems
  - Initially  $V=\{S\}$ , where  $S$  is the start node,  $E=\{\}$
  - On expanding  $S$ , its *successor nodes* are generated and added to  $V$  and associated *arcs added to  $E$*
  - Process continues until a goal node is found
- Nodes represent a *partial solution* path (+ cost of partial solution path) from  $S$  to the node
  - From a node there may be many possible paths (and thus solutions) with this partial path as a prefix

# State-space search algorithm

*;; problem describes the start state, operators, goal test, and operator costs*

*;; queueing-function is a comparator function that ranks two states*

*;; general-search returns either a goal node or failure*

```
function general-search (problem, QUEUEING-FUNCTION)
  nodes = MAKE-QUEUE (MAKE-NODE (problem.INITIAL-STATE) )
  loop
    if EMPTY(nodes) then return "failure"
    node = REMOVE-FRONT(nodes)
    if problem.GOAL-TEST (node.STATE) succeeds
      then return node
    nodes = QUEUEING-FUNCTION (nodes, EXPAND (node,
      problem.OPERATORS) )
  end
```

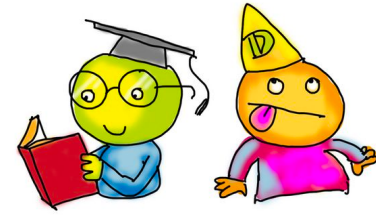
*;; Note: The goal test is NOT done when nodes are generated*

*;; Note: This algorithm does not detect loops*

# Key procedures to be defined

- EXPAND
  - Generate a node's successor nodes, adding them to the graph if not already there
- GOAL-TEST
  - Test if state satisfies all goal conditions
- QUEUEING-FUNCTION
  - Maintain ranked list of nodes that are candidates for expansion
  - Changing definition of the QUEUEING-FUNCTION leads to different search strategies

# Informed vs. uninformed search



## Uninformed search strategies (blind search)

- Use no information about likely *direction* of a goal
- Methods: breadth-first, depth-first, depth-limited, uniform-cost, depth-first iterative deepening, bidirectional

## Informed search strategies (heuristic search)

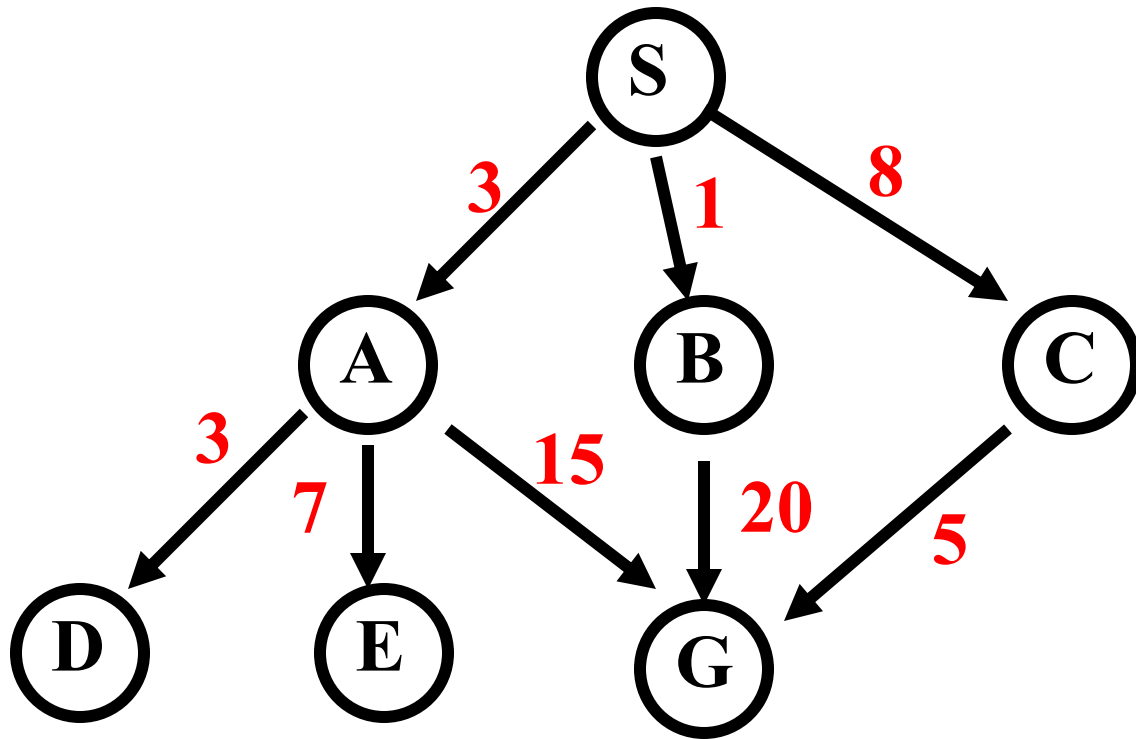
- Use information about domain to (try to) (usually) head in the general direction of goal node(s)
- Methods: hill climbing, best-first, greedy search, beam search, algorithm A, algorithm A\*



# Evaluating search strategies

- **Completeness**
  - Guarantees finding a solution whenever one exists
- **Time complexity** (worst or average case)
  - Usually measured by *number of nodes expanded*
- **Space complexity**
  - Usually measured by maximum size of graph/tree during the search
- **Optimality/Admissibility**
  - If a solution is found, is it **guaranteed** to be an optimal one, i.e., one with minimum cost

# Example of uninformed search strategies



Consider this search space where S is the start node and G is the goal. Numbers are arc costs.

# Classic uninformed search methods

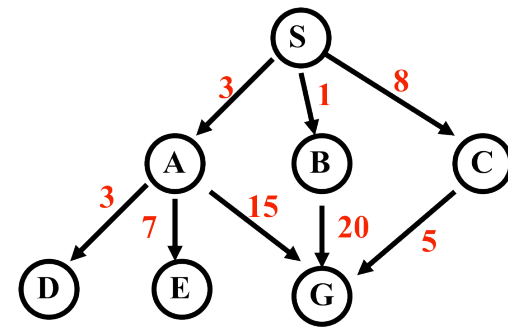
- The four classic uninformed search methods
  - Breadth first search (BFS)
  - Depth first search (DFS)
  - Uniform cost search (*generalization of BFS*)
  - Iterative deepening (*blend of DFS and BFS*)
- To which we can add another technique
  - Bi-directional search (*hack on BFS*)

# Breadth-First Search

- Enqueue nodes in **FIFO** (first-in, first-out) order
- **Complete**
- **Optimal** (i.e., admissible) finds shortest path, which is optimal if all operators have same cost
- **Exponential time and space complexity,  $O(b^d)$** , where  $d$  is depth of solution;  $b$  is branching factor (i.e., # of children)
- Takes a **long time to find solutions** with large number of steps because must explore all shorter length possibilities first

# Breadth-First Search

weighted arcs



Expanded node	Nodes list (aka Fringe)
	{ S <sup>0</sup> }
S <sup>0</sup>	{ A <sup>3</sup> B <sup>1</sup> C <sup>8</sup> }
A <sup>3</sup>	{ B <sup>1</sup> C <sup>8</sup> D <sup>6</sup> E <sup>10</sup> G <sup>18</sup> }
B <sup>1</sup>	{ C <sup>8</sup> D <sup>6</sup> E <sup>10</sup> G <sup>18</sup> G <sup>21</sup> }
C <sup>8</sup>	{ D <sup>6</sup> E <sup>10</sup> G <sup>18</sup> G <sup>21</sup> G <sup>13</sup> }
D <sup>6</sup>	{ E <sup>10</sup> G <sup>18</sup> G <sup>21</sup> G <sup>13</sup> }
E <sup>10</sup>	{ G <sup>18</sup> G <sup>21</sup> G <sup>13</sup> }
G <sup>18</sup>	{ G <sup>21</sup> G <sup>13</sup> }

*Notation*

**G<sup>18</sup>**

G is node; 18 is cost of shortest known path from start node S

Note: we typically don't check for goal until we expand node  
 Solution path found is S A G , cost 18  
 Number of nodes expanded (including goal node) = 7

# Breadth-First Search

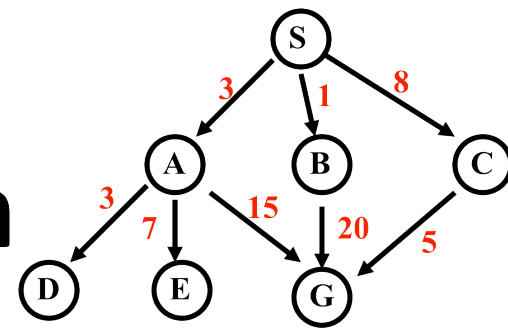
**Long time to find solutions** with many steps: we must look at all shorter length possibilities first

- Complete search tree of depth  $d$  where nodes have  $b$  children has  $1 + b + b^2 + \dots + b^d = (b^{(d+1)} - 1)/(b-1)$  nodes =  $O(b^d)$
- Tree of depth 12 with branching 10 has more than a trillion nodes
- If BFS expands 1000 nodes/sec and nodes uses 100 bytes, then it may take 35 years to run and uses 111 terabytes of memory!

# Depth-First (DFS)

- Enqueue nodes on nodes in **LIFO** (last-in, first-out) order, i.e., use stack data structure to order nodes
- **May not terminate w/o depth bound**, i.e., ending search below fixed depth  $D$  (depth-limited search)
- **Not complete** (with or w/o cycle detection, with or w/o a cutoff depth)
- **Exponential time**,  $O(b^d)$ , but **linear space**,  $O(bd)$
- Can find **long solutions quickly** if lucky (and **short solutions slowly** if unlucky!)
- On reaching deadend, can only back up one level at a time even if problem occurs because of a bad choice at top of tree

# Depth-First Search



Expanded node	Nodes list
	$\{ S^0 \}$
$S^0$	$\{ A^3 B^1 C^8 \}$
$A^3$	$\{ D^6 E^{10} G^{18} B^1 C^8 \}$
$D^6$	$\{ E^{10} G^{18} B^1 C^8 \}$
$E^{10}$	$\{ G^{18} B^1 C^8 \}$
$G^{18}$	$\{ B^1 C^8 \}$

Solution path found is S A G, cost 18

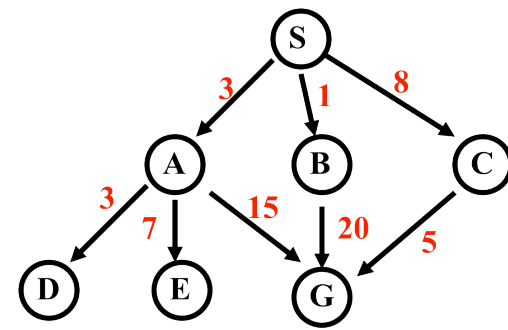
Number of nodes expanded (including goal node) = 5



# Uniform-Cost Search (UCS)

- Enqueue nodes by **path cost**. i.e., let  $g(n)$  = cost of path from *start* to current node  $n$ . Sort nodes by increasing value of  $g(n)$ .
- Also called [Dijkstra's Algorithm](#), similar to *Branch and Bound Algorithm* from operations research
- **Complete (\*)**
- **Optimal/Admissible (\*)**  
Depends on goal test being applied *when node is removed from nodes list*, not when its parent node is expanded & node first generated
- **Exponential time and space complexity,  $O(b^d)$**

# Uniform-Cost Search



Expanded node

Nodes list

	$\{ S^0 \}$
$S^0$	$\{ B^1 A^3 C^8 \}$
$B^1$	$\{ A^3 C^8 G^{21} \}$
$A^3$	$\{ D^6 C^8 E^{10} G^{18} G^{21} \}$
$D^6$	$\{ C^8 E^{10} G^{18} G^{21} \}$
$C^8$	$\{ E^{10} G^{13} G^{18} G^{21} \}$
$E^{10}$	$\{ G^{13} G^{18} G^{21} \}$
$G^{13}$	$\{ G^{18} G^{21} \}$

Solution path found is S C G, cost 13

Number of nodes expanded (including goal node) = 7

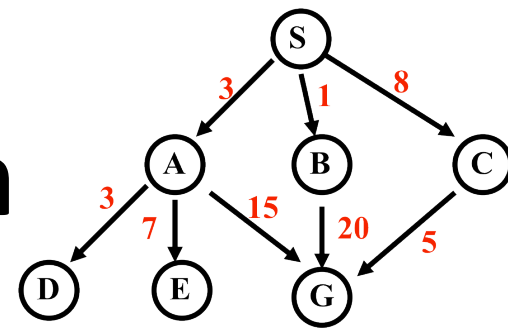
# Depth-First Iterative Deepening (DFID)

- Do DFS to depth 0, then (if no solution) DFS to depth 1, etc.
- Usually used with a tree search
- **Complete**
- **Optimal/Admissible** if all operators have unit cost, else finds shortest solution (like BFS)
- Time complexity a bit worse than BFS or DFS  
Nodes near top of search tree generated many times, but since almost all nodes are near tree bottom, worst case time complexity still exponential,  $O(b^d)$

# Depth-First Iterative Deepening (DFID)

- If branching factor is  $b$  and solution is at depth  $d$ , then nodes at depth  $d$  are generated once, nodes at depth  $d-1$  are generated twice, etc.
  - Hence  $b^d + 2b^{(d-1)} + \dots + db \leq b^d / (1 - 1/b)^2 = O(b^d)$ .
  - If  $b=4$ , worst case is  $1.78 * 4^d$ , i.e., 78% more nodes searched than exist at depth  $d$  (in worst case)
- **Linear space complexity**,  $O(bd)$ , like DFS
- Has advantages of BFS (completeness) and DFS (i.e., limited space, finds longer paths quickly)
- Preferred for **large state spaces** where **solution depth is unknown**

# How they perform



- **Depth-First Search:**

- 4 Expanded nodes: S A D E G
- Solution found: S A G (cost 18)

- **Breadth-First Search:**

- 7 Expanded nodes: S A B C D E G
- Solution found: S A G (cost 18)

- **Uniform-Cost Search:**

- 7 Expanded nodes: S A D B C E G
- Solution found: S C G (cost 13)

*Only uninformed search that worries about costs*

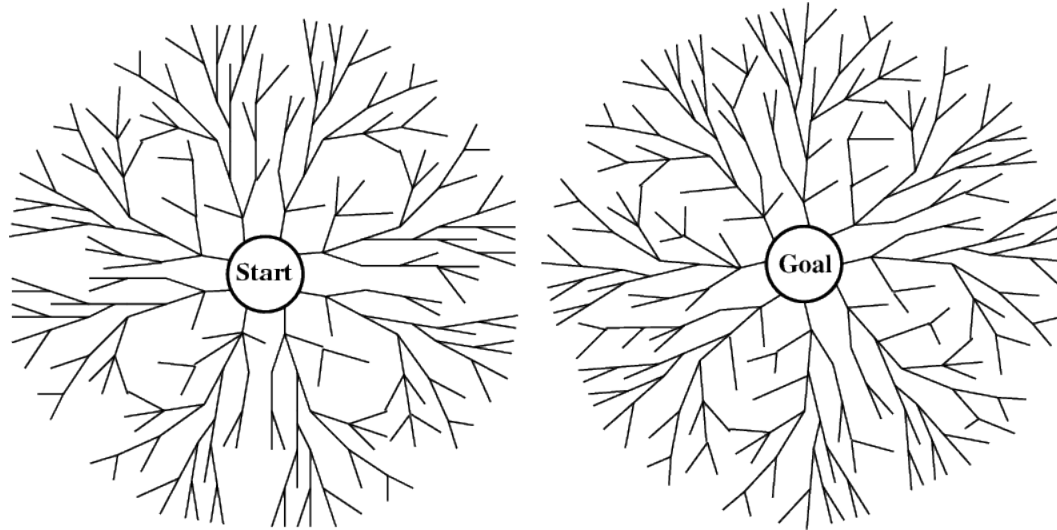
- **Iterative-Deepening Search:**

- 10 nodes expanded: S S A B C S A D E G
- Solution found: S A G (cost 18)

# Searching Backward from Goal

- Usually a successor function is reversible
  - i.e., can generate a node's predecessors in graph
- If we know a single goal (rather than a goal's properties), we could search backward to the initial state
- It might be more efficient
  - Depends on whether the graph fans in or out

# Bi-directional search



- Alternate searching from the start state toward the goal and from the goal state toward the start
- Stop when the frontiers intersect
- Works well only when there are unique start & goal states
- Requires ability to generate “predecessor” states
- Can (sometimes) lead to finding a solution more quickly

# Comparing Search Strategies

Criterion	Breadth-First	Uniform-Cost	Depth-First	Depth-Limited	Iterative Deepening	Bidirectional (if applicable)
Time	$b^d$	$b^d$	$b^m$	$b^l$	$b^d$	$b^{d/2}$
Space	$b^d$	$b^d$	$bm$	$bl$	$bd$	$b^{d/2}$
Optimal?	Yes	Yes	No	No	Yes	Yes
Complete?	Yes	Yes	No	Yes, if $l \geq d$	Yes	Yes