CS 4700: Foundations of Artificial Intelligence

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Informed Search

Readings R&N - Chapter 3: 3.5 and 3.6
Search strategies determined by choice of node (in queue) to expand

**Uninformed** search:
- Distance to goal not taken into account

**Informed** search:
- Information about cost to goal taken into account

Aside: “Cleverness” about what option to explore next, almost seems a hallmark of intelligence. E.g., a sense of what might be a good move in chess or what step to try next in a mathematical proof. We don’t do blind search…
Basic idea: State evaluation function can effectively guide search.

Also in multi-agent settings. (Chess: board eval.)

Reinforcement learning: Learn the state eval function.

Perfect “heuristics,” eliminates search.

Approximate heuristics, significantly reduces search.
Best (provably) use of search heuristic info: Best-first / A* search.
Best-first search
Greedy best-first search
A* search
Heuristics
How to take information into account? Best-first search.

Idea: use an evaluation function for each node

– Estimate of “desirability” of node
– Expand most desirable unexpanded node first (“best-first search”)
– Heuristic Functions:
  • $f$: States $\rightarrow$ Numbers
  • $f(n)$: expresses the quality of the state $n$
    – Allows us to express problem-specific knowledge,
    – Can be imported in a generic way in the algorithms.
– Use uniform-cost search. See Figure 3.14 but use $f(n)$ instead of path cost $g(n)$. Note: $g(n) =$ cost so far to reach $n$
– Queuing based on $f(n)$:
  Order the nodes in fringe in decreasing order of desirability

Special cases:
  • greedy best-first search
  • A* search
Romanian path finding problem

Searching for good path from Arad to Bucharest, what is a reasonable “desirability measure” to expand nodes on the fringe?

Base eg on GPS info. No map needed.
Greedy best-first search

Evaluation function at node $n$, $f(n) = h(n)$ (heuristic)

$= \text{estimate of cost from } n \text{ to goal}$

e.g., $h_{SLD}(n) = \text{straight-line distance from } n \text{ to Bucharest}$

Greedy best-first search expands the node that appears to have shortest path to goal.

Idea: those nodes may lead to solution quickly.

Similar to depth-first search: It prefers to follow a single path to goal (guided by the heuristic), backing up when it hits a dead-end.
Greedy best-first search example
Greedy best-first search example
Greedy best-first search example
Greedy best-first search example

Is it optimal?

What are we ignoring?

Also, consider going from Iasi to Fagaras – what can happen?

So, Arad --- Sibiu --- Fagaras --- Bucharest

140 + 99 + 211 = 450
Properties of greedy best-first search

**Complete?** No – can get stuck in loops, e.g.,

Iasi $\rightarrow$ Neamt $\rightarrow$ Iasi $\rightarrow$ Neamt...

But, complete in finite space with repeated state elimination.

**Time?** $O(b^d)$ (imagine nodes all have same distance estimate to goal)

but a good heuristic can give dramatic improvement $\rightarrow$ Becomes more similar to depth-first search, with reduced branching.

**Space?** $O(b^m)$ -- keeps all nodes in memory

**Optimal?** No!

$\begin{align*}
b & : \text{maximum branching factor of the search tree} \\
d & : \text{depth of the least-cost solution} \\
m & : \text{maximum depth of the state space (may be } \infty \text{)}
\end{align*}$

**How can we fix this?**
A* search

Note: Greedy best-first search expands the node that appears to have shortest path to goal. But what about cost of getting to that node? Take it into account!

Idea: avoid expanding paths that are already expensive

Evaluation function \( f(n) = g(n) + h(n) \)

- \( g(n) = \) cost so far to reach \( n \)
- \( h(n) = \) estimated cost from \( n \) to goal
- \( f(n) = \) estimated total cost of path through \( n \) to goal

Aside: do we still have “looping problem”?
Iasi to Fagaras:
Iasi \( \rightarrow \) Neamţ \( \rightarrow \) Iasi \( \rightarrow \) Neamţ...

No! We’ll eventually get out of it. \( g(n) \) keeps going up.
Using: \( f(n) = g(n) + h(n) \)
Using: $f(n) = g(n) + h(n)$

A* search example
Using: \( f(n) = g(n) + h(n) \)

A* search example
Using: $f(n) = g(n) + h(n)$
**Using:** $f(n) = g(n) + h(n)$

A* search example

Bucharest appears on the fringe but not selected for expansion since its cost (450) is higher than that of Pitesti (417).

Important to understand for the proof of optimality of A*

What happens if $h(\text{Pitesti}) = 150$?
**A* search example**

\[ f(n) = g(n) + h(n) \]

Claim: Optimal path found!

1) Can it go wrong?

2) What’s special about “straight distance” to goal?

    **It underestimates true path distance!**

3) What if all our estimates to goal are 0? Eg \( h(n) = 0 \) \( \rightarrow \) \( f(n) = g(n) \)

4) What if we overestimate?

5) What if \( h(n) \) is true distance (\( h^*(n) \))?

What is \( f(n) \)?

Shortest dist. through \( n \) --- perfect heuristics --- no search

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**Note:** Bucharest twice in tree.

**Note:** Greedy best first

Arad --- Sibiu --- Fagaras --- Bucharest

Uniform cost search

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**Note:** Bucharest twice in tree.
**A* properties**

Under some reasonable conditions for the heuristics, we have:

**Complete**
- Yes, unless there are infinitely many nodes with $f(n) < f(\text{Goal})$

**Time**
- Sub-exponential growth when
- So, a good heuristics can bring $|h(n) - h^*(n)| \leq O(\log h^*(n))$ significantly!

**Space**
- Fringe nodes in memory. Often exponential. Solution: IDA*

**Optimal**
- Yes (under admissible heuristics; discussed next)
- Also, optimal use of heuristic information!

**Widely used. E.g. Google maps.**  
*Provably: Can’t do better!*

After almost 40 yrs, still new applications found.

Also, optimal use of heuristic information.
**Heuristics: (1) Admissibility**

A heuristic $h(n)$ is **admissible** if for every node $n$,

$$h(n) \leq h^*(n),$$

where $h^*(n)$ is the **true** cost to reach the goal state from $n$.

An admissible heuristic **never overestimates** the cost to reach the goal,

i.e., it is **optimistic**. (But no info of where the goal is if set to 0.)

**Example:** $h_{SLD}(n)$ (never overestimates the actual road distance)

**Note:** it follows that $h(\text{goal}) = 0.$

**Evaluation function**

$$f(n) = g(n) + h(n)$$

**Note:** less optimistic heuristic push nodes to be expanded later. Can prune a lot more.
Heuristics: (2) Consistency

A heuristic is **consistent (or monotone)** if for every node $n$, every successor $n'$ of $n$ generated by any action $a$,

$$h(n) \leq c(n,a,n') + h(n')$$

(form of the triangle inequality)

If $h$ is consistent, we have

$$f(n') = g(n') + h(n')$$

$$= g(n) + c(n,a,n') + h(n')$$

$$\geq g(n) + h(n)$$

$$= f(n)$$

\[\rightarrow\] sequence of nodes expanded by $A^*$ is in nondecreasing order of $f(n)$

\[\rightarrow\] the **first** goal selected for expansion must be an optimal goal.

i.e., $f(n)$ is non-decreasing along any path.

Note: Monotonicity is a stronger condition than admissibility. Any consistent heuristic is also admissible. (Exercise 3.29)
A*: Tree Search vs. Graph Search

TREE SEARCH (See Fig. 3.7; used in earlier examples):

If $h(n)$ is admissible, A* using tree search is optimal.

GRAPH SEARCH (See Fig. 3.7) A modification of tree search that includes an “explored set” (or “closed list”; list of expanded nodes to avoid re-visiting the same state); if the current node matches a node on the closed list, it is discarded instead of being expanded. In order to guarantee optimality of A*, we need to make sure that the optimal path to any repeated state is always the first one followed:

If $h(n)$ is monotonic, A* using graph search is optimal.
(proof next)

Reminder: Bit of “sloppiness” in fig. 3.7. Need to be careful with nodes on frontier; allow repetitions or as in Fig. 3.14.

(see details page 95 R&N)

See notes on intuitions of optimality of A* (at the end of lecture notes)
Example: Contrasting A* with Uniform Cost (Dijkstra’s algorithm)

Example: The shortest route from Hannover to Munich

1) Dijkstra’s alg., i.e., A* with h(n)=0 (Uniform cost search)
2) A* search

Example thanks to Meinolf Sellmann
Shortest Paths in Germany

Hannover
Bremen
Hamburg
Kiel
Leipzig
Schwerin
duesseldorf
Rostock
Frankfurt
Dresden
Berlin
Bonn
Stuttgart
Muenchen
Shortest Paths in Germany

Hannover 0
Bremen 120
Hamburg 155
Kiel ∞
Leipzig 255
Schwerin 270
Dusseldorf 320
Rostock ∞
Frankfurt 365
Dresden ∞
Berlin ∞
Bonn ∞
Stuttgart ∞
Muenchen ∞
Shortest Paths in Germany

Hannover  0
Bremen  120
Hamburg  155
Kiel  240
Leipzig  255
Schwerin  270
Duesseldorf  320
Rostock  ∞
Frankfurt  365
Dresden  8
Berlin  8
Bonn  8
Stuttgart  8
Muenchen  8
Shortest Paths in Germany

Hannover  0
Bremen    120
Hamburg   155
Kiel      240
Leipzig   255
Schwerin  270
Duesseldorf 320
Rostock   ∞
Frankfurt 365
Dresden   395
Berlin    440
Bonn      ∞
Stuttgart ∞
Muenchen  690
Shortest Paths in Germany

Hannover 0
Bremen 120
Hamburg 155
Kiel 240
Leipzig 255
Schwerin 270
Duesseldorf 320
Rostock 360
Frankfurt 365
Dresden 395
Berlin 440
Bonn 545
Stuttgart 565
Muenchen 690

Note: route via Frankfurt longer than current one.
Shortest Paths in Germany

Hannover 0
Bremen 120
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### Shortest Paths in Germany

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<thead>
<tr>
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<th>Distance</th>
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<tr>
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<tr>
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Shortest Paths in Germany

- Hannover: 0
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- Frankfurt: 365
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We just solved a shortest path problem by means of the algorithm from Dijkstra.

If we denote the cost to reach a state \( n \) by \( g(n) \), then Dijkstra chooses the state \( n \) from the fringe that has minimal cost \( g(n) \). (I.e., uniform cost search.)

The algorithm can be implemented to run in time \( O(n \log n + m) \) where \( n \) is the number of nodes, and \( m \) is the number of edges in the graph. (As noted before, in most settings \( n \) (number of world states) and \( m \) (number of possible transitions between world states) grow exponentially with problem size. E.g. \((N^2-1)\)-puzzle.)

Approach is rather wasteful. Moves in circles around start city. Let’s try A* with non-zero heuristics (i.e., straight distance).
Shortest Paths in Germany
Shortest Paths in Germany

Hannover 0 + 610 = 610
Bremen 120 + 720 = 840
Hamburg 155 + 720 = 875
Kiel ∞ + 750 = ∞
Leipzig 255 + 410 = 665
Schwerin 270 + 680 = 950
Duesseldorf 320 + 540 = 860
Rostock ∞ + 740 = ∞
Frankfurt 365 + 380 = 745
Dresden ∞ + 400 = ∞
Berlin ∞ + 590 = ∞
Bonn ∞ + 480 = ∞
Stuttgart ∞ + 180 = ∞
Muenchen ∞ + 0 = ∞
Shortest Paths in Germany

<table>
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</thead>
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<tr>
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<td>(\infty + 750 = \infty)</td>
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<td>365 + 380 = 745</td>
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<td>Bonn</td>
<td>(\infty + 480 = \infty)</td>
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Berlin: $440 + 590 = 1030$
Bonn: $\infty + 480 = \infty$
Stuttgart: $\infty + 180 = \infty$
Muenchen: $690 + 0 = 690$
Heuristics
Slide the tiles horizontally or vertically into the empty space until the configuration matches the goal configuration.

What’s the branching factor? (slide “empty space”)

About 3, depending on location of empty tile:
- middle → 4; corner → 2; edge → 3

The average solution cost for a randomly generated 8-puzzle instance → about 22 steps.
So, search space to depth 22 is about $3^{22} \approx 3.1 \times 10^{10}$ states.

Reduced to by a factor of about 170,000 by keeping track of repeated states
(9!/2 = 181,440 distinct states) note: 2 sets of disjoint states. See exercise 3.4

But: 15-puzzle → $10^{13}$ distinct states!

We’d better find a good heuristic to speed up search! Can you suggest one?

Note: “Clever” heuristics now allow us to solve the 15-puzzle in a few milliseconds!
E.g., for the 8-puzzle:

\[ h_1(n) = \text{number of misplaced tiles} \]
\[ h_2(n) = \text{total Manhattan distance} \]
(i.e., no. of steps from desired location of each tile)

\[ h_1(\text{Start}) = ? \]
\[ h_2(\text{Start}) = ? \]

8

\[ 3 + 1 + 2 + 2 + 2 + 3 + 3 + 2 = 18 \]

True cost = 26

Why are heuristics admissible?
Which is better?
How can we get the optimal heuristics? (Given \( H_{\text{opt}}(\text{Start}) = 26 \). How would we find the next board on the optimal path to the goal?)

Desired properties heuristics:

1. consistent (admissible)
2. As close to opt as we can get (sometimes go a bit over...)
3. Easy to compute! We want to explore many nodes.

Note: each empty-square-move = 1 step tile move.
Comparing heuristics

Effective Branching Factor, $b^*$

- If A* generates $N$ nodes to find the goal at depth $d$
  $$b^* = \text{branching factor such that a uniform tree of depth } d \text{ contains } N+1 \text{ nodes (we add one for the root node that wasn’t included in } N)$$
  $$N+1 = 1 + b^* + (b^*)^2 + \ldots + (b^*)^d$$

  **E.g., if A* finds solution at depth  5 using 52 nodes, then the effective branching factor is 1.92.**

- $b^*$ close to 1 is ideal
  - because this means the heuristic guided the A* search is closer to ideal (linear).
  - If $b^*$ were 100, on average, the heuristic had to consider 100 children for each node
  - Compare heuristics based on their $b^*$
Comparison of heuristics

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**Figure 4.8** Comparison of the search costs and effective branching factors for the **ITERATIVE-DEEPPING-SEARCH** and **$A^*$** algorithms with $h_1, h_2$. Data are averaged over 100 instances of the 8-puzzle, for various solution lengths.

$d$ – depth of goal node

**h2 indeed significantly better than h1**
h₂ is always better than h₁

- Because for any node, n, \( h_2(n) \geq h_1(n) \). (Why?)

We say h₂ dominates h₁

It follows that h₁ will expand at least as many nodes as h₂.

Because:

Recall all nodes with \( f(n) < C^* \) will be expanded.

This means all nodes, \( h(n) + g(n) < C^* \), will be expanded.

So, all nodes n where \( h(n) < C^* - g(n) \) will be expanded.

All nodes h₂ expands will also be expanded by h₁ and because h₁ is smaller, others may be expanded as well.
Inventing admissible heuristics: Relaxed Problems

Can we generate $h(n)$ automatically?

– Simplify problem by reducing restrictions on actions

A problem with fewer restrictions on the actions is called a relaxed problem
Examples of relaxed problems

Original: A tile can move from square A to square B iff
(1) A is horizontally or vertically adjacent to B \textit{and} (2) B is blank

Relaxed versions:
- A tile can move from A to B if A is adjacent to B ("overlap"; Manhattan distance)
- A tile can move from A to B if B is blank ("teleport")
- A tile can move from A to B ("teleport and overlap")

Key: Solutions to these relaxed problems can be computed \underline{without search}
and therefore provide a heuristic that is easy/fast to compute.

This technique was used by ABSOLVER (1993) to invent heuristics for the 8-puzzle better than existing ones and it also found a useful heuristic for famous Rubik’s cube puzzle.
The cost of an optimal solution to a relaxed problem is an admissible heuristic for the original problem. Why?

1) The optimal solution in the original problem is also a solution to the relaxed problem (satisfying in addition all the relaxed constraints). So, the solution cost matches at most the original optimal solution.

2) The relaxed problem has fewer constraints. So, there may be other, less expensive solutions, given a lower cost (admissible) relaxed solution.

What if we have multiple heuristics available? I.e., $h_1(n), h_2(n), \ldots$

$$h(n) = \max \{h_1(n), h_2(n), \ldots, h_m(n)\}$$

If component heuristics are admissible so is the composite.
Inventing admissible heuristics: Learning

Also automatically learning admissible heuristics using machine learning techniques, e.g., inductive learning and reinforcement learning.

Generally, you try to learn a “state-evaluation” function or “board evaluation” function. (How desirable is state in terms of getting to the goal?) Key: What “features / properties” of state are most useful?

More later…
**Uninformed search:**
(1) Breadth-first search (2) Uniform-cost search
(3) Depth-first search (4) Depth-limited search
(5) Iterative deepening search (6) Bidirectional search

**Informed search:**
(1) Greedy Best-First
(2) A*
Heuristics allow us to scale up solutions dramatically!

*Can now search combinatorial (exponential size) spaces with easily 10^15 states and even up to 10^100 or more states.*

*Especially, in modern heuristics search planners (eg FF).*

Before informed search, considered totally infeasible.

Still many variations and subtleties:

There are conferences and journals dedicated solely to search.

Lots of variants of A*.

Research in A* has increased dramatically since A* is the key algorithm used by map engines.

Also used in path planning algorithms (autonomous vehicles), and general (robotics) planning, problem solving, and even NLP parsing.

The end
A*: Tree Search vs. Graph Search

TREE SEARCH (See Fig. 3.7; used in earlier examples):

If $h(n)$ is admissible, A* using tree search is optimal.

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If $h(n)$ is monotonic, A* using graph search is optimal.
(proof next)

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(see details page 95 R&N)
Intuition: Contours of A*

A* expands nodes in order of increasing $f$ value.

Gradually adds "$f$-contours" of nodes.
Contour $i$ has all nodes with $f \leq f_i$, where $f_i < f_{i+1}$

Note: with uniform cost ($h(n)=0$) the bands will be circular around the start state.

A* expands all nodes with $f(n)<C^*$
Uniform-cost ($h(n)=0$) expands in circles.

Completeness (intuition)
As we add bands of increasing $f$, we must eventually reach a band where $f$ is equal to the cost of the path to a goal state. (assuming $b$ finite and step cost exceed some positive finite $\varepsilon$).

Optimality (intuition)
1st solution found (goal node expanded) must be an optimal one since goal nodes in subsequent contours will have higher $f$-cost and therefore higher $g$-cost (since $h(goal)=0$).
Theorem:
A* used with a *consistent* heuristic ensures optimality with graph search.
Proof:

(1) If \( h(n) \) is consistent, then the values of \( f(n) \) along any path are non-decreasing. See consistent heuristics slide.

(2) Whenever \( A^* \) selects a node \( n \) for expansion, the optimal path to that node has been found. Why?
   
   Assume \textit{not}. Then, the optimal path, \( P \), must have some not yet expanded nodes. (*) Thus, on \( P \), there must be an unexpanded node \( n' \) on the current frontier (because of graph separation; fig. 3.9; frontier separates explored region from unexplored region). But, because \( f \) is nondecreasing along any path, \( n' \) would have a lower \( f \)-cost than \( n \) and would have been selected first for expansion before \( n \). Contradiction.

From (1) and (2), it follows that the sequence of nodes expanded by \( A^* \) using Graph-Search is in non-decreasing order of \( f(n) \). Thus, the first goal node selected must have the optimal path, because \( f(n) \) is the true path cost for goal nodes (\( h(Goal) = 0 \)), and all later goal nodes have paths that are at least as expensive. QED

(*) requires a bit of thought. Must argue that there cannot be a shorter path going only through expanded nodes (by contradiction).
Note: Termination / Completeness

Termination is guaranteed when the number of nodes with \( f(n) \leq f^* \) is finite.

Non-termination can only happen when

- There is a node with an infinite branching factor, or

- There is a path with a finite cost but an infinite number of nodes along it.

  • Can be avoided by assuming that the cost of each action is larger than a positive constant \( d \)
A* Optimal in Another Way

It has also been shown that A* makes optimal use of the heuristics in the sense that there is no search algorithm that could expand fewer nodes using the heuristic information (and still find the optimal / least cost solution.

So, A* is “the best we can get.”

Note: We’re assuming a search based approach with states/nodes, actions on them leading to other states/nodes, start and goal states/nodes.