INTELLIGENT AGENTS

CHAPTER 2
Reminders

Assignment 0 (lisp refresher) due 1/28

Lisp/emacs/AIMA tutorial: 11-1 today and Monday, 271 Soda
Outline

◊ Agents and environments
◊ Rationality
◊ PEAS (Performance measure, Environment, Actuators, Sensors)
◊ Environment types
◊ Agent types
**Agents and environments**

Agents include humans, robots, softbots, thermostats, etc.

The agent function maps from percept histories to actions:

\[ f : \mathcal{P}^* \rightarrow \mathcal{A} \]

The agent program runs on the physical architecture to produce \( f \)
Vacuum-cleaner world

Percepts: location and contents, e.g., \([A, Dirty]\)

Actions: \(Left, Right, Suck, NoOp\)
A vacuum-cleaner agent

<table>
<thead>
<tr>
<th>Percept sequence</th>
<th>Action</th>
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<tbody>
<tr>
<td>[A, Clean]</td>
<td>Right</td>
</tr>
<tr>
<td>[A, Dirty]</td>
<td>Suck</td>
</tr>
<tr>
<td>[B, Clean]</td>
<td>Left</td>
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<tr>
<td>[B, Dirty]</td>
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function Reflex-Vacuum-Agent( [location, status] ) returns an action

if status = Dirty then return Suck
else if location = A then return Right
else if location = B then return Left

What is the right function?
Can it be implemented in a small agent program?
Rationality

Fixed performance measure evaluates the environment sequence
- one point per square cleaned up in time $T$?
- one point per clean square per time step, minus one per move?
- penalize for $> k$ dirty squares?

A rational agent chooses whichever action maximizes the expected value of the performance measure given the percept sequence to date

Rational $\neq$ omniscient
- percepts may not supply all relevant information
Rational $\neq$ clairvoyant
- action outcomes may not be as expected
Hence, rational $\neq$ successful

Rational $\Rightarrow$ exploration, learning, autonomy
To design a rational agent, we must specify the task environment

Consider, e.g., the task of designing an automated taxi:

Performance measure?

Environment?

Actuators?

Sensors?
To design a rational agent, we must specify the task environment

Consider, e.g., the task of designing an automated taxi:

**Performance measure??** safety, destination, profits, legality, comfort, . . .

**Environment??** US streets/freeways, traffic, pedestrians, weather, . . .

**Actuators??** steering, accelerator, brake, horn, speaker/display, . . .

**Sensors??** video, accelerometers, gauges, engine sensors, keyboard, GPS, . . .
Internet shopping agent

Performance measure??

Environment??

Actuators??

Sensors??
Internet shopping agent

**Performance measure??** price, quality, appropriateness, efficiency

**Environment??** current and future WWW sites, vendors, shippers

**Actuators??** display to user, follow URL, fill in form

**Sensors??** HTML pages (text, graphics, scripts)
## Environment types

<table>
<thead>
<tr>
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<th>Episodic??</th>
<th>Static??</th>
<th>Discrete??</th>
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## Environment types

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| Deterministic | Yes | No  | Partly | No |
| Episodic | No  | No  | No  | No |
| Static | Yes | Semi | Semi | No |
| Single-agent | Yes | Yes | No  | No |

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The environment type largely determines the agent design

The real world is (of course) partially observable, stochastic, sequential, dynamic, continuous, multi-agent
Agent types

Four basic types in order of increasing generality:
- simple reflex agents
- reflex agents with state
- goal-based agents
- utility-based agents

All these can be turned into learning agents
Simple reflex agents

Agent

Environment

Sensors

What the world is like now

Condition–action rules

What action I should do now

Actuators
Example

function REFLEX-VACUUM-AGENT([location, status]) returns an action

    if status = Dirty then return Suck
    else if location = A then return Right
    else if location = B then return Left

(setq joe (make-agent :name 'joe :body (make-agent-body)
                      :program (make-reflex-vacuum-agent-program)))

(defun make-reflex-vacuum-agent-program ()
    #'(lambda (percept)
        (let ((location (first percept)) (status (second percept)))
            (cond ((eq status 'dirty) 'Suck)
                  ((eq location 'A) 'Right)
                  ((eq location 'B) 'Left))))
Reflex agents with state

Agent

Environment

State

How the world evolves

What my actions do

Condition–action rules

What the world is like now

What action I should do now

Actuators

Sensors
Example

function REFLEX-VACUUM-AGENT([location,status]) returns an action
static: last_A, last_B, numbers, initially ∞
   if status = Dirty then ...

(defun make-reflex-vacuum-agent-with-state-program ()
   (let ((last-A infinity) (last-B infinity))
      #'(lambda (percept)
         (let ((location (first percept)) (status (second percept)))
            (incf last-A) (incf last-B)
            (cond
               ((eq status 'dirty)
                  (if (eq location 'A) (setq last-A 0) (setq last-B 0))
                  'Suck)
               ((eq location 'A) (if (> last-B 3) 'Right 'NoOp))
               ((eq location 'B) (if (> last-A 3) 'Left 'NoOp))))))
Goal-based agents

Agent

- State
  - How the world evolves
  - What my actions do
  - Goals

Environment

- Sensors
  - What the world is like now
  - What it will be like if I do action A

Actuators

- What action I should do now
Utility-based agents

Agent

State

What the world is like now

What it will be like if I do action A

How happy I will be in such a state

What action I should do now

How the world evolves

What my actions do

Utility

Sensors

Environment

Actuators

Chapter 2
Learning agents

Agent

Environment

Performance standard

Critic

Sensors

Feedback

Changes

Knowledge

Learning goals

Problem generator

Performance element

Actuators
Summary

Agents interact with environments through actuators and sensors.

The agent function describes what the agent does in all circumstances.

The performance measure evaluates the environment sequence.

A perfectly rational agent maximizes expected performance.

Agent programs implement (some) agent functions.

PEAS descriptions define task environments.

Environments are categorized along several dimensions:

Several basic agent architectures exist:
  reflex, reflex with state, goal-based, utility-based.