Assignment 8

The due date for submitting this assignment has passed. As per our records you have not submitted this assignment.

1) Planning and problem solving methods can often solve the same sorts of problems; however, planning and problem solving are different because of ______ point(s). Select one:
   - A. Methods
   - B. Only planning
   - C. Both Statements I and II
   - D. Only Statement I

No, the answer is incorrect.

2) Type of planning which involves selecting an action whose precursors are met until a goal state is reached. ______ point(s)
   - A. Repetition Planning
   - B. Progressive Planning
   - C. Stave-Space Planning
   - D. Graph-based Planning

No, the answer is incorrect.

3) Situation calculus is a classic of First Order Logic. Which of the following statements holds for situation calculus? ______ point(s)
   - A. Situation and actions are explicitly taken to be objects in the domain.
   - B. Doing true to represent beliefs about changing world.
   - C. Successor state assertion specifies truth value of facts in the current state.
   - D. All of the above.

No, the answer is incorrect.

4) STRIPS is an alternative representation to the partial situation calculus for planning. Actions are not represented explicitly as part of the world state. ______ point(s)
   - A. Only Statement I is correct.
   - B. Statements I and II
   - C. Only Statement II is correct.
   - D. None

No, the answer is incorrect.

5) A planner that can represent plans in which some steps are ordered with respect to each other and other steps are unordered to be ______ point(s)
   - A. Uninformed Planner
   - B. Partial Order Planner
   - C. Graph Plan
   - D. Total Order Planner

No, the answer is incorrect.

6) ________ can solve the Sequential Anomaly. ______ point(s)
   - A. State-Space Planner
   - B. Hierarchical Planner
   - C. Stav-Space Planner
   - D. Non-hierarchical Planner

No, the answer is incorrect.

7) Plan space planning is also referred to as ______ planning ______ point(s)
   - A. Action
   - B. Minimax
   - C. Goal Stack
   - D. Linear

No, the answer is incorrect.

8) In a planning graph, a pair of mutually exclusive propositions in the same layer is linked through the __________ edge ______ point(s)
   - A. Heads
   - B. Heads
   - C. Positive
   - D. Pre-condition

No, the answer is incorrect.

9) GrepPlan is a two phase algorithm; Planning Graph Construction followed by Subgoals Elimination. What did the first phase achieve ______ point(s)
   - A. Defining the search space
   - B. Some kind of irreducibility analysis on the green problem.
   - C. Both A and B above
   - D. None of A and B above

No, the answer is incorrect.

10) A* search is greedy reduces search space, and is more efficient at solving large problems. It is a kind of ______ planning ______ point(s)
    - A. State-space
    - B. Regular
    - C. Heuristic
    - D. Stav-Space

No, the answer is incorrect.