EUROPA$_2$: Plan Database Services for Planning and Scheduling Applications

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Abstract

NASA missions require solving a wide variety of planning and scheduling problems with temporal constraints; simple resources such as robotic arms, communications antennae and cameras; complex replenishable resources such as memory, power and fuel; and complex constraints on geometry, heat and lighting angles. Planners and schedulers that solve these problems are used in ground tools as well as onboard systems. The diversity of planning problems and applications of planners and schedulers precludes a "one-size fits all" solution. However, many of the underlying technologies are common across planning domains and applications. We describe CAPR, a formalism for planning that is general enough to cover a wide variety of planning and scheduling domains of interest to NASA. We then describe EUROPA$_2$, a software framework implementing CAPR. EUROPA$_2$ provides efficient, customizable Plan Database Services that enable the integration of CAPR into a wide variety of applications. We describe the design of EUROPA$_2$ from the perspective of both modeling, customization and application integration to different classes of NASA missions.

Introduction

Inspired by NASA's missions that require solving a wide variety of planning and scheduling problems, each of which must be integrated into different operating environments, we set out to formalize and implement a planning framework on which many of these mission scenarios can be built. Our intuition is that many other real-world problems are similar and that such a framework will be widely applicable. The Remote Agent Experiment (RAX) on the Deep Space 1 Spacecraft (Muscettola et al. 1998), (Jönsson et al. 2000) featured a planner on board a spacecraft that required reasoning about accumulated thrust, spacecraft attitude relative to navigation aids, and the state of hardware resources like cameras. The EO-1 ScienceCraft experiment (Tran et al. 2004) is another onboard planner that must reason about onboard memory and CPU resources, communications opportunities to replenish memory, and options for satisfying science goals. Controllers onboard terrestrial Unmanned Autonomous Vehicles (UAVs) such as Rotorcraft (Whalley et al. 2003) must reason about the state of communication systems, onboard payloads such as imagers, and how image acquisition constrains intended maneuvers such as banks and climbs, in the face of complex flight dynamics. Autonomy systems (Dias, Lemai, & Muscettola 2003), (Despoys & Ingrand 1999) as well as ground tools (Bresina et al. 2003) for robots like the Mars Exploration Rovers (MER) require reasoning about thermal models, available power and remaining memory, as well as the location of the rover relative to intended science targets and how to choose from among available science operations. Image Processing planning (Golden et al. 2003) requires reasoning about feasible image manipulation operations, available web services, as well as the state of underlying computer file systems, including the location of inputs and outputs of processing operations.

The diversity of planning problems and applications of planners and schedulers precludes a "one-size fits all" solution. Different planning paradigms apply more naturally to different planning problems, and different applications require different planning services. For example, planetary rover domains require one form of path planning, UAVs require quite different forms of path planning, while satellite domains such as EO-1 do not require path planning at all. Path planning generally requires reasoning about concepts that are immutable with respect to time, and so does image processing. Although domains such as EO-1, MER, and RAX require reasoning with resources, EO-1 and MER feature onboard memory resources, while the RAX does not. In either of these cases, reasoning about time is important. Furthermore, in onboard systems such as spacecraft, UAVs and rovers, planner response time may preclude expensive algorithms that guarantee optimality. Additionally, some applications require that the planner provide incomplete solutions, such as those where the planner interfaces with an intelligent executive that is able to "fill in the blanks". Human operators or other autonomous sub-systems may look at plans, and request changes or explanations, ultimately leading to new planning problems.

Despite the considerable diversity of planning problem classes, planners and applications, there is considerable commonality among planning and scheduling problems,
solvers and applications. This commonality can be aggregated into a set of plan services that we call the Plan Database that are provided to build such applications. Consider the scenarios illustrated in Figure 1. The first is an application of automated planning where the input planning problem is solved by a Planner to produce an acceptable partial plan. The role of the Planner is to perform the search steps for resolving flaws. Thus it interacts with a partial plan by imposing and retracting restrictions. All operations are made on the Plan Database which stores the partial plan. The second is an application of automated planning in concert with a User. The User may introduce goals into a plan, and change or undo decisions previously made by a Planner. Additionally, a User may employ a Planner to work on the current partial plan. In this case changes are also made in response to queries and operations on the Plan Database. In the last figure, planning technology is deployed for plan execution. A partial plan may be used by an Executive for execution. In such a scenario, the partial plan is updated throughout execution. The Executive may employ incomplete search to refine the partial plan as it goes. A Planner may be employed to repair a plan or develop a refinement of the plan as the mission progresses. In each of the cases described, clients (i.e., Planner, User, Executive) leverage the services of a common server, the Plan Database.

We have created a robust formal framework called Constraint Planning with Resources (CAPR) that supports many commonly used representational primitives and reasoning engines. We describe this formalism in the next section of the paper. This formal framework provides the underpinnings for the Plan Database, called the Extensible Universal Remote Operations Architecture (EUROPA2). This idea is similar to the approach taken by the CLARATy robotics control architecture (Nesnas et al. 2003) or MDS (Dvorak et al. 2000), as well as constraint reasoning systems such as ILOG (ILOG 1996).

Applications will require customization of the Plan Database to support only those primitives needed by the domain (e.g., time, resources), and to implement an appropriate planner (e.g., an optimizing planner versus one with real-time guarantees). We describe how to build domain models for EUROPA2 as well as how to build custom planners. In the final sections of the paper, we discuss related work, and conclude with a discussion of our future plans.

Constraint-Based Planning with Resources

In this section we describe Constraint Based Planning with Resources (CAPR). CAPR is a modification of Constraint-Based Attribute and Interval Planning (CAIP) (Frank & Jonsson 2003), a formalism that employs variables and constraints as first-class objects to describe complex planning domains. CAPR relaxes some of the more restrictive assumptions made in CAIP, resulting in a more generally applicable formalism. In particular, we include general resources as first-class citizens in the planning formalism, and separate subgoaling and causal models from the resource model. We will show later that we lose none of the representational power of CAIP by having made these changes.

We first describe the formalism in grounded terms, in which all primitives are predicates. We then provide a more easily managed formalism using constraints and variables as primitives.

Grounded case

A token is a logical statement of the form \( \text{hold}(s, e, p(a_1, ..., a_k)) \) where \( t_s < t_e \) are start and end times, \( p \) is a predicate symbol and \( a_1, ..., a_k \) are parameter values. Tokens generalize actions and state, and merely assert that some property of interest is true for a period of time.

A resource \( R \) is defined by a tuple \((i, l, R)\) where \( i \) is the initial level, \( l \) is the minimum level, \( L \) is the maximum.

A transaction is a numerical change in a resource over a specified interval. It is defined as a tuple \((R, s, e, \delta)\) where \( R \) is a resource, \( s \leq e \) are times, and \( \delta \) is a function mapping timepoints \( t, t \in [t_s, t_e] \), to numerical values.

An instantaneous transaction is a transaction where \( t_s = t_e \) and is referred to as \((R, t, \delta)\).

A configuration rule is an implication of the form \( T \Rightarrow C_1 \lor C_2 \lor \cdots \lor C_n \) where \( T \) is a token and each \( C_i \) is a conjunction of the form \( S_{i, 1} \land \cdots \land S_{i, k_i} \) where each \( S_{i,j} \) is either a token or a transaction.

**Definition 1** A planning domain \( D \) is a tuple \((T, R, C)\), where \( T \) is a set of tokens, \( R \) is a set of resources, and \( C \) is a set of configuration rules.

**Definition 2** A resource profile for a given plan \( P \) and resource \((i, l, R)\) from the domain for that plan is a function \( \lambda_R(t) \) defined as follows:

\[
\lambda_R(t) = \begin{cases} i & t < t_s \\ l & t_s \leq t < t_e \\ R & t \
\end{cases}
\]
We first define a cumulative impact function $\Delta_i$ for each transaction $T_i$ in $P$ as follows:

- If $T_i$ is a non-instantaneous transaction, define $\Delta_i$ as the integral of $\delta$, defined as $\Delta_i(t) = 0$ for $t < t_s$, $\Delta_i(t) = \int_{t_s}^{t} \delta(\tau)$ for $t \in [t_s, t_e]$ and $\Delta_i(t) = \int_{t_e}^{t} \delta(\tau)$ for $t > t_e$.

- If $T_i$ is an instantaneous transaction, define $\Delta_i(t) = 0$ if $t < t_s$, and $\Delta_i(t) = \delta(t)$ if $t \geq t_s$.

Then, for each time point $t$, $\lambda_R(t) = \sum \delta_i(t)$.

A resource profile $\lambda_R(t)$ for a resource $(i_R, l_R, R)$ and plan $P$ is valid if $l_R \leq \lambda_R(t) \leq L_R$ for all timepoints $t$.

A partial plan is a set of tokens along with the applicable transactions defined by the domain rules.

A partial plan $Q$ is an extension of a partial plan $P$ if each token in $P$ can be mapped to a matching token in $Q$.

**Definition 3** A partial plan $P$ is valid if:

- for each token $T$ in $P$, and for each configuration rule $T \Rightarrow C_1 \vee \cdots \vee C_n$, there exists a $j \in [1, n]$ such that where $C_j = S_{i,1} \wedge \cdots \wedge S_{i,k_j}$, each of the tokens and transactions $S_{i,1}, \ldots, S_{i,k_j}$ are in $P$.
- the resource profile for every resource is valid.

A planning problem is a pair $(D, P)$ where $D$ is a planning domain and $P$ is a partial plan. A solution to the planning problem is a plan $Q$ that is a valid extension of $P$.

**Lifted case**

The grounded formalism is inconvenient since it may require large numbers of token descriptions and rules. It is more effective to compress these definitions by using variables and constraints as the primitive elements of the planning domain descriptions.

A domain is a list of primitive values. A predicate definition is a tuple $(p, D_1, \ldots, D_k)$ of a predicate $p$ and a (possibly empty) set of domains, which define the number of arguments and the argument domains for the predicate.

A resource definition, like before, is a tuple $(i_R, l_R, R)$ where $l$ is the initial level, $l_R$ is the minimum level and $L_R$ is the maximum.

A token specifies a predicate instantiation. A planning domain $P$ is an extension of a partial plan $P$ if each token in $P$ can be mapped to a matching token in $Q$.

A planning problem is a pair $(D, P)$ where $D$ is a planning domain and $P$ is a partial plan. A solution to the planning problem is a plan $Q$ that is a valid extension of $P$.

**Decision Model and Completeness results**

We next describe the flaw mechanisms and the associated search path options. In backwards chaining, unsatisfied preconditions are flaws that must be resolved before achieving an complete plan. In PCOL planning, the flaws are open conditions and unresolved threats. In CAPR, flaws are either undetermined constraints, undetermined resources, or unsupported tokens. As we will see below, flaw resolution for all three of these cases is accomplished by constraining the domain values of variables.

**Undetermined constraints**: Suppose we have a partial plan $P$ with a variable $v$ in a constraint $c$ that is undetermined. Normally, unassigned variables are simply assigned single values until constraints are known to be satisfied. However, it is possible to proceed by imposing constraints that restrict variables values.
Undetermined resources: Suppose we have a partial plan \( P \) with a resource that is undetermined. In most cases it is too expensive to calculate \( L_{\text{max}, R}(t) \) and \( L_{\text{min}, R}(t) \), because it would require calculating all of the grounded extensions \( Q_i \). Thus we must bound above \( L_{\text{max}, R}(t) \) and bound below \( L_{\text{min}, R}(t) \) to determine validity. When all transactions are grounded we can determine \( L_{\text{max}, R}(t) \) and \( L_{\text{min}, R}(t) \); for this reason, flaws on resources are usually satisfied by assigning transaction timepoint variables. Suppose the problem is such that no incomplete token decisions will ever arise as flaws are resolved. In this case, we are left with a scheduling problem. If we further restrict ourselves to the case of scheduling instantaneous transactions, we can use techniques such as those described in (Frank 2004; Muscettola 2002) to tightly bound \( L_{\text{max}, R}(t) \) and \( L_{\text{min}, R}(t) \). In some circumstances, partial orders of transactions are sufficient to guarantee that the resource is provably valid. For these cases, flaw resolution can be accomplished by only ordering transaction timepoints.

Unsupported tokens: Finally, suppose we have a partial plan \( P \) with a token \( T = (s, e, p, a_1, ..., a_k) \) that is unsupported. There is at least one rule whose head unifies with \( T \). For each such rule, one of the disjuncts \( B_i \) must be chosen in order to satisfy the rule. This can be thought of as a value choice for a variable. Each disjunct consists of a conjunct \( G_{i,j} \), where \( G_{i,j} \) is a predicate description or transaction. If \( G_{i,j} \) is a transaction, a resource must be chosen for the transaction; this too is a variable choice. If \( G_{i,j} \) is a token, then let \( V \) be the set of tokens that can be unified with \( G_{i,j} \), along with one extra element, \( T \), representing the use of a new token. Then, the decision to be made is which element of \( V \) to select. Once again, this can be viewed as a variable choice. Note that only if \( T \) is chosen, resulting in a new token, will any new compatibilities apply to tokens in the plan \( P \). However, if \( G_{i,j} \) is unified with \( V \in V \), all the constraints in \( G_{i,j} \) are added to constrain the variables in \( V \) and \( T \). These constraints generalize causal links in the same manner as CAIP.

Completeness results: We are now ready to show that this decision model is sufficient for solving planning problems in CAPR. As was true in the CAIP framework (Frank & Jönsson 2003), there may be solutions to a planning problem that are not reachable given the domain description and the decision model. However, we can still prove that there is a plan that is a complete and valid extension of the domain description and decision model such that the unreachable plan is an extension of this plan. This situation arises because there is nothing in the formalism to prevent adding arbitrary tokens that don’t have compatibilities associated with them.

**Theorem 1** Given a finite planning domain \((P, R, C)\) and a finite length partial plan \( P \). Assume that \( Q \) is a complete and valid finite length extension of \( P \). Then, there exists a plan \( R \), that is a complete and valid extension of \( P \) such that a sequence of flaw resolutions transforms \( P \) into \( R \), and \( Q \) is an extension of \( R \).

**Proof 1** As in (Frank & Jönsson 2003), we will use \( Q \) as a “heuristic” to describe how to transform \( P \) into \( Q \). While applicable:

- If a token \( T \) of \( P \) is unsupported, there is a supported token \( V \) in \( Q \) that matches \( T \); use this token to satisfy \( T \), either by choosing a disjunct \( B_i \), by satisfying a conjunct \( S_{i,j}; C_{i,j} \) with an existing matching token in \( P \), or by adding a new token to \( P \).
- If a variable \( v \) is unassigned, there is a matching variable \( w \) in \( Q \); use this variable to assign the value of \( v \). Note that this covers the case of deciding which available resource a transaction is assigned to.
- If a constraint among variables in \( P \) has not been imposed, use \( Q \) to impose that constraint. Note that this covers the case of ordering timepoints.

Since \( Q \) is finite and \( P \), at each stage, is a subset of \( Q \), the process halts with a complete plan \( R \). And, since the set of constraints in \( P \), at each stage, are a subset of those in \( Q \), constraint validity is obvious. The only remaining part is to show that all resources are valid in \( P \). First, it is easy to see that a resource in \( P \) cannot be violated, as \( Q \) is an extension of \( P \) and the profile is defined based on all extensions. Second, the resource cannot be neither violated nor valid, as that will give rise to flaws and the process does not halt until there are no other flaws. So, the resource envelopes must also be valid. Thus, \( R \) is a complete valid extension of \( P \), and is a subset of \( Q \); thus any tokens, constraints or transactions in \( Q \) can be added to \( R \) with impunity.

**EUROPA**

In order to successfully deploy CAPR in many different contexts, we adopt the strategy of providing a Plan Database motivated by the CAPR formalism. The Plan Database provides services that support description of planning domains, allow implementation of a wide variety of planners and schedulers, as well as provide information about the plans as well as the planning process to applications. These services include:

- Domain modeling: for describing planning domains
- Partial plan representation: for maintaining partial plans
- Flaw generation: for generating flaws from a partial plan
- Flaw resolution: for resolving flaws in a partial plan
- Plan assessment: for determining plan completeness or violations
- Constraint propagation: for propagating the consequences of constraints

To meet the needs of missions and research projects, the design of the Plan Database must meet the following critical design goals:

- Efficiency - ensure low latency for operations and queries.
- Flexibility - ensure services can be selected and flexibly integrated.
- Extensibility - ensure services can be enhanced to meet the needs of research or mission applications.
We have implemented EUROPA2, a Plan Database that meets these requirements. To illustrate EUROPA2 we present a planning domain loosely based on the MER mission. We assume the application in question is one of producing daily activity plans for operation of a planetary surface robot named Rover. Rover is a mobile robot equipped with a range of instruments to sample and study a geological site. A Rover processes plans for taking rock samples in various locations within a given survey area. It has on board a battery, and can replenish its energy levels using solar power.

Planning Domain Descriptions with NDDL

Planning domain descriptions for EUROPA2 are written in New Domain Description Language (NDDL). In this section we will describe NDDL and show how the syntax translates to the CAPR formalism.

Rooted in the formal framework of CAPR, NDDL provides an object-oriented syntax and semantics that makes it convenient to express sophisticated relationships among elements of a partial plan. There are a number of additional capabilities in NDDL which offer greater convenience and efficiency for the modeler.

Predicates A predicate in CAPR defined as \((p, D_1, \ldots, D_k)\) is directly described in NDDL. For example, a Rover might be at a Location, or it might be moving from one location to another. The predicate At can be introduced with:

```java
predicate At(Rover r; Location l);
```

where \(r\) and \(l\) refer to the set of all rovers and the set of all locations respectively. Similarly we can introduce the predicate Going:

```java
predicate Going(Rover r; Location from; Location to);
```

Rover and Location are user-defined types which may be expressed using enumeration:

```java
enum Rover {spirit, opportunity}

or through the more expressive use of an abstract data type, or class:

class Rover {}

class Location {
  int x;
  int y;
  Location(int x, int y) {
    x = x;
    y = y;
  }
}
```

Thus, class describes an unchanging object. Instances of classes, i.e. objects, may be introduced thus:

```java
Rover spirit = new Rover();
Rover opportunity = new Rover();
Location rock = new Location(1, 1);
Location hill = new Location(2, 3);
Location lander = new Location(5, 8);
Location martian-city = new Location(6, 6);
```

For convenience, predicates may be defined directly on a class. Predicates introduce time-varying properties of a class. The set of instances of that class are implicitly a parameter of the predicate, and are accessed through the built-in variable object. Thus we may concisely restate our predicate definitions by augmenting the Rover class:

```java
class Rover {
  predicate At(Location l);
  predicate Going(Location from; Location to);
}
```

**Compatibilities** Suppose that Rover is not permitted to go to the same location it is leaving. Furthermore, suppose that every Going must be followed by an At and vice versa. To express these domain rules, we introduce a compatibility for each predicate. Recall that a token is defined in CAPR as \((s, e, p, a_1, \ldots, a_k)\). The compatibility for At given below shows the two Going subgoals with constraints imposed on their predicate parameters (including the previously described implicit object variable) and its start and end variables.

```java
Rover::At{
  // Require a Going token on same
  // object which succeeds this token
  subgoal(Going g);
  eq(g.start, end); // Equate timepoints
  eq(g.from, end); // Equate parameters
  eq(g.object, object);
  // Require a Going token on same
  // object which succeeds this token
  subgoal(Going g);
  eq(g.end, start); // New constraint
  eq(g.to, 1); // New constraint
  eq(g.object, object);
}
```

NDDL directly supports specifying temporal constraints with Allen relations augmented with metric time. We use the Allen relations directly as shorthand for creating a subgoal token with the associated temporal constraints. Furthermore, we can use the object variable to specify the constraint that the At token must be on the same object as the Going token. We thus express the compatibilities for Going more concisely as follows:

```java
Rover::Going{
  neg(to, from); // to != from
  meets(object.At a0);
  eq(a0.start, to);
  eq(a0.object, object);
}
```

Suppose the Rover could either go to another location or stay at the current location and take a panoramic image. In NDDL we model this by using a disjunctive rule where we explicitly create a boolean variable to represent the disjunction.

```java
Rover::At{
  // disjunctive rule for successor
  // token: false implies Going, true
  // implies taking
  bool next;
  if (next==false) {
    meets(object.Going a6);
  }
```
Resources and Transactions  To illustrate the use of resources in NDDL, we introduce a battery which stores energy produced from solar panels and allows energy to be consumed by rover activities.

```java
class Rover {
    Resource battery;
    Rover() {
        battery = new Battery(10, 3, 30);
    }
}
```

Now declare a predicate for power generation:

```java
predicate generatePower(Resource r; float rate) {
    // produce transaction at the end
    ends(r.transaction tx);
    // relation to derive instantaneous
    // change from rate and duration
    calcProduction(tx.quantity, rate, start, end);
}
```

Finally, the compatibility for Going can be augmented with a consumption transaction on the battery where the quantity is based on the distance travelled:

```java
subgoal(object.battery.transaction tx);
// Consume at the beginning
eq(tx.object, object.mutex);
```

Timelines  In CAIP, Timelines were constructs used to ensure that a set of predicates were mutually exclusive, as well as ensuring that one of these predicates held at any time in valid plans. In CAPR, and subsequently, EUROPA2, timelines are no longer first class members of the paradigm. However, the notion of ensuring mutual exclusion among predicates is very common. Therefore, it's useful to have a convenient short-hand for defining classes, where all their tokens are mutually exclusive. This is done by declaring a class as an extension of a special construct called a Timeline. Using this construct is exactly the same as defining mutual exclusion unary resources and appropriate resource transactions, but is more concise and can be implemented efficiently. In our example, the use of Timeline gives a more concise model:

```java
class Rover extends Timeline {
    predicate At{Location 1;)
    predicate Going{Location from;
        ...}
}
```

Static Objects  Other useful features offered by NDDL are local compatibility variables, and the use of classes to capture information that is static over time. These features prove useful in the Rover planning domain where a further restriction is imposed such that only some paths in the survey area are traversable. The abstract data type for the set of paths can be specified as:

```java
class Path {
    Location loc1;
    Location loc2;
    Path(Location l1, Location l2) {
        loc1 = l1;
        loc2 = l2;
    }
}
```

and the set can be populated with instances using object allocation e.g.:

```java
Path p1 = new Path(rock, hill);
Path p2 = new Path(hill, lander);
Path p3 = new Path(martian-city, lander);
```

An additional rule can be introduced for the Going predicate to enforce the path existence requirement:

```java
Rover::Going{
    Path p : {
```

The variable $p$ is comparable to a predicate parameter variable, though it is only introduced locally in a rule, and need not be grounded in a complete partial plan. The initial values for $p$ will be $p_1$, $p_2$, and $p_3$. These values will be filtered through constraint propagation. Should there be no path, the domain of $p$ will be empty and a violation will occur.

**Partial Plans in EUROPA₂**

In this section we discuss the representation and manipulation of partial plans in EUROPA₂.

**Tokens and Open Conditions** A partial plan for the rover planning domain is created with the following statement:

```plaintext
goal (Rover .Going G);
```

This introduces a token $G$ for the predicate $Going$ defined on the class $Rover$. The results is the partial plan $p = \{(G),{}\}$. All tokens in a partial plan are represented as Active Tokens in a EUROPA₂ plan database. All Open Conditions can be inferred from the partial plan and the model. Open Conditions are represented in a EUROPA₂ plan database as Inactive Tokens. Figure 2 illustrates the states and transitions of tokens in EUROPA₂. As is the case with $G$, a token is Active immediately when introduced by an actor external to the plan database. Alternatively, a token is initially Inactive when introduced by a compatibility. As described in the previous section on the decision model, an Inactive Token must be resolved by either merging it with an existing Active Token (i.e. choosing a resolver from the set of tokens in the plan $V$) or by inserting it into the partial plan via activation (i.e. using the resolver $T$).

With $G$ the following variables are introduced to the Plan Database. The default variables of $G$ are introduced with all tokens:

- **start** - the start time for the token. In this example the domain is [-inf,+inf].
- **end** - the end time for the token. In this example, the domain is [-inf,+inf].
- **duration** - the duration of the token. This does not add any new information to the definition of a token since it can be derived from the start and end variables but it proves convenient. In this example, the domain is [1,+inf].

**Constraints** Further requirements can be imposed in the initial partial plan. For example, $spirit$ must be at location $rock$ at time 0:

```plaintext
// Introduce token A
goal(Rover.At A); // constrain location variable
eq(A.obj, rock); // c0
// Constraint object variable
eq(A.object, spirit); // c1
// Constrain start <= 0 <= end
leq(A.start, 0); // c2
leq(0, A.end); // c3
```

Taken together, this partial plan, $p$, is given by the tuple $\{(G,A),\{c0, c1, c2, c3\}\}$.

**Inference with Compatibilities** Compatibilities are only matched with active tokens. A simplified version of a previously described compatibility for $Rover::Going$ is listed...
The head of the above compatibility is matched immediately upon introduction of $G$ to the partial plan. Execution of the body yields an open condition $A$, a set of constraints and a single transaction $T$. These elements, and the relations between them, are illustrated in Figure 3. The relations are annotated with line numbers indicating where they arise from explicit declarations in the compatibility. Line 1 produces a constraint among the parameter variables of $G$. Line 2 introduces the open condition $A$. It also imposes an equality constraint between the object variables of $G$ and $A$. Line 3 equates the parameter variables $A.t$ and $G.t$. Line 4 requires a new transaction $T$ in the database. EUROPAZ does not currently support interval transactions, so we also generate an implicit constraint equaling $T.start$ and $T.end$. Finally, Line 5 equates the start times of $G$ and $T$. Note that disjunctive compatibilities are modeled by variables, so these variables would be introduced as flaws when matching a compatibility to an Active token, and only when these variables are decided do we introduce the corresponding tokens and constraints.

**Flaw Generation and Resolution**
CAPR identifies flaws as undetermined resources, unsupported tokens, and undetermined flaws respectively. Events provide immediate access to changes within the Plan Database. EUROPAZ these translate to resource, token, and variable flaws on a given set of dynamic and/or infinite variables are excluded.

**Variable Flaw** - unbound variables are resolved by assigning values directly or restricting values with constraints.

**Plan Assessment**
Some applications may have different models of interaction with EUROPAZ and will want to impose relaxations on the set of flaws that should be resolved by the planner. For example, imagine a multi-agent system where each planning agent shares a single model, yet each is specialized to resolve flaws only in a sub-domain of expertise. Each planning agent would be done planning when it finishes resolving all the flaws it needs to resolve. EUROPAZ provides a flexible decision management framework to filter the set of flaws that need to be resolved for a partial plan to be complete. Semantically, these operations amount to a relaxation of the strict interpretation of the set of flaws in a plan. The filtering criteria allow clients to indicate:

- **temporal restrictions** - all flaws outside a given planning horizon are excluded.
- **predicate restrictions** - all flaws derived from a given set of predicates are excluded.
- **variable restrictions** - variable flaws on a given set of dynamic and/or infinite variables are excluded.
- **custom restrictions** - specialized filter conditions may be developed and integrated as needed by the client.

**Constraint Propagation**
EUROPAZ is built upon the constraint propagation infrastructure illustrated in Figure 4. The model statement:

```plaintext
introduces a Constraint with the ConstrainedVariables T.quantity, from, to.
```

Each constrained variable has a domain which is propagated. A change in a domain triggers a message in the variable, which is passed on to the ConstraintEngine. Each constraint is registered with a Propagator allowing customized propagation strategies for different constraints. This framework allows for specialization domains, constraints, variables and propagators to be integrated in an open and flexible manner. The framework borrows heavily from the design of the CHOCO kernel (Laburthe & the OCRE Research Group 2001). EUROPAZ provides a library of useful constraints together with a default propagator which delegates constraint enforcement to each individual constraint. It also includes a resource propagator which propagates transaction loads on resources, and a temporal propagator which propagates temporal constraints using a simple temporal network.
EUROPA2 Architecture

We now describe the overall EUROPA2 System Architecture and discuss how it accomplishes design goals described earlier.

Figure 5 describes the internals of the EUROPA2 Plan Database operating as a server to one or more clients. The server is an assembly of EUROPA2 components integrated for the needs of the particular application. The Plan Database provides a facade for interacting with the server at the abstraction level of primitives in CAPR i.e. tokens, transactions, constraints, resources, variables. The Constraint Engine and related components are utilized to propagate relations among variables and detect violations. Standard and customized constraints and propagators can be freely integrated or omitted. The Rules Engine is triggered by changes in the partial plan i.e. token activation and variable binding. The Schema is the in-memory store for the domain model. It is used by the plan database to enforce type restrictions and by the rules engine to match and execute compatibilities. EUROPA2 includes a chronological backtracking planner as a standard client component, though many applications develop their own clients. The Decision Manager uses a flaw filter specification to manage the set of flaws for a client.

Customizability EUROPA2 is highly customizable. If a problem does not require resources, support for resources may be omitted. If a problem does not require compatibilities (e.g. a scheduling problem), the rules engine can be omitted. If temporal constraints are not important in a problem, the temporal propagator may be removed and/or replaced with the default propagator. Only required constraints need to be registered. This form of customization is useful as it allows systems to avoid incurring costs for components that are not required. EUROPA2 also provides a language to customize the system for new domain models. Furthermore, heuristic and flaw specifications are also provided. Finally, an open API ensures flexibility in how EUROPA2 is integrated.

Extensibility EUROPA2 is highly extensible. As new problems are encountered, or new algorithms are developed, there are many ways to integrate new capabilities as specialized components e.g. constraints, propagators, resources. This is essential for success in research and mission deployments.

Speed EUROPA2 has produced significant gains in speed over EUROPA. The primary contributors to the improvement arise from:

- fast interfaces & specialized implementations. The ability to tune implementations using inheritance provides speed improvements in key areas such as operations on domains.
- efficient merging. Resolving open conditions by merging is an important operation governing the efficiency of the system. EUROPA2 accomplishes this with an algorithm that avoids redundant constraints arising in the plan database.
- incremental relaxation. When relaxing a variable (e.g. retracting a decision), EUROPA2 uses localized propagation to relax reachable variables in the constraint graph.
- direct support for static facts. EUROPA2 uses objects to capture static facts. We provide a means to naturally reference or require objects through variables and the pattern for existential quantification. EUROPA used single predicate timelines to capture this information, incurring a high overhead and compounding the problems of inefficient merging.

Future Work

We have presented a formalization of constraint-based planning with resources and described EUROPA2 a framework that implements the formulation. The current implementation of EUROPA2 is being used by the Intelligent Systems Program to demonstrate advanced robotic capabilities in the field. We have plans to make this software available for use in research and mission deployments. We are currently working on many extensions. On the theoretical side, we plan to develop domain independent heuristics for resource-cognizant planners. The main challenge is the identification of useful heuristics and the translation of static CSP heuristics into a dynamic CSP setting. We also plan to work on obtaining soundness and completeness results for different subgoaling configurations. We know that there is a relationship between the theory behind the languages of PDDL, TAL, NDDL, and SAS+, and we plan to identify and describe the relationship so that we can better understand how EUROPA2 compares to these systems.

We plan to extend our modeling language in two ways: 1.
provide better modeling support for time-invariant relationships; 2. provide means to describe optimization criteria. Some of the domains, such as the image processing domain require the specification and reasoning about relationships that are immutable with respect to time. We currently provide the means only to specify data but relationships among the data are assumed to change with respect to time. Furthermore, many planning applications require not only finding a plan but finding a plan with respect to certain optimization criteria. We plan to extend NDDL to allow describing optimization criteria such as minimize makespan or minimize resource consumption.

Finally, we have numerous plans for extending our implementation. We plan to extend the set of planning services provided to include domain analysis techniques such as reachability. We are already working on a PDDL frontend for EUROPA2. Furthermore, we plan to extend the set of services provided by adding direct support for lifted local search planning; more specialized constraint reasoners; and hybrid solvers. The current EUROPA2 implementation has been designed to deal with consistent as well as inconsistent states but only a backtracking planner has been implemented to date. We need to extend the notion of flaws to include violations to be able to handle local search methods, and test whether the implementation holds.

Related Work
EUROPA2 is certainly not the only planner that can plan with resources and express resources as first class citizens. IxTeT already plans with resources, however, IxTeT requires modeling state changing properties as attributes. EUROPA2 allows the expression and reasoning of arbitrary objects, not just objects that behave like attributes. IxTeT, however, provides more reasoning support for resources than CAPR in that they define how to prune "dominated" transaction ordering decisions: 1) they use some graph theory to infer that only certain decisions are necessary, then 2) eliminate "dominated" decision (e.g. if $a < b \rightarrow c < b$ then $a < b$ is not considered.) However, we were unable to find soundness and completeness proofs of planning with resources in IxTeT.

ZENO (Pemberthy & Weld 1994) is a sound and complete planner that handles actions with temporal quantified preconditions and effects. ZENO can reason about deadline goals, piecewise-linear continuous change, external events and, to a limited extent, simultaneous actions. In particular, actions are allowed to overlap in time only when their effects do not interfere. From what we can tell, there is no special purpose reasoning on constraints, and instead, variable assignments ensure that non-linear equations reduce to linear equations. In contrast, EUROPA2 provides 1. a language for expressing declarative resources, 2. ability to express richer types of resources, and 3. ability to handle any type of constraint.

Given the success of PDDL (Fox & Long 2003) in the academic community, PDDL has been extended to cope with problems of increasing size and complexity. However, the extensions have been driven by the capability of planners that have participated in the competitions. PDDL thus, is able to describe plan metrics, a capability that we plan to include in EUROPA2. PDDL, however, has a process-driven time semantics and is unable to deal with preconditions that hold over specific intervals of time and effects that can happen at arbitrary points during action execution. In EUROPA2 resources are first-class citizens and can be fully described declaratively, and relationships between other entities in the plan and resources can be expressed as constraints. In PDDL, resources are represented by numeric fluents, which provide advantages and disadvantages. The ability to represent numeric fluents means that planners can then subgoal based on internal numeric states. However, it is difficult and awkward to express a unified view of resources and their properties, which means that planners cannot take advantage of dedicated reasoning algorithms to solve problems with resources. PDDL is a stronger language for specifying goals, e.g. it is possible in PDDL to express goals with disjunctions. In EUROPA2 it is only possible to describe goals in terms of whether they are required or optional, but arbitrary formulae are not allowed.

The Coupled Layered Architecture for Robotic Autonomy CLARATy, is an architecture with goals to: 1. Capture and integrate a wide range of technologies; 2. Leverage existing tools; 3. Leverage experience and tools of the larger software development community; 4. Apply appropriate design patterns to the domain; 5. Provide an infrastructure that enables rapid robotic development; and 6. Capture experience of technologists implementation. The goals of EUROPA2 are very similar. Having deployed the previous generation of EUROPA2 in field tests and missions we have learned that different missions require different functionality, yet they require high performance. EUROPA2 is being developed in order to support the development of generic algorithms, reduce the need for recurring problems for every deployment, simplify the integration of new technologies, use the same framework across deployments, increase functionality by leveraging a more mature base. These are the same motivations that drive CLARATy. CLARATy is a two-layered architecture the first layer is the decision layer that includes the planner, models, and heuristics. The second layer provides the abstraction of the specific robot components. The first layer is based on ASPEN/CASPER system architecture which is similar to EUROPA2’s architecture in that the search engine performs operations on an activity database which in turn performs constraint propagation over parameters and temporal constraints. ASPEN provides a framework where you should able to implement a local repair planner and a chronological backtracking planner using some the same components.

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