On Bootstrapping Local Search with Trail-Markers

Pang C. Chen*
Sandia National Laboratories
Albuquerque, NM 87185 USA
pchen@sandia.gov

Abstract

We study a simple, general framework for search called bootstrap search, which is defined as global search using only a local search procedure along with some memory for learning intermediate subgoals. We present a simple algorithm for bootstrap search, and provide some initial theory on its performance. In our theoretical analysis, we develop a random digraph problem model and use it to make some performance predictions and comparisons. We also use it to provide some techniques for approximating the optimal resource bound on the local search to achieve the best global search. We validate our theoretical results with empirical demonstration on the 15-puzzle. We show how to reduce the cost of a global search by 2 orders of magnitude using bootstrap search. We also demonstrate a natural but not widely recognized connection between search costs and the lognormal distribution.

1 Introduction

We study a simple, general framework for search called bootstrap search, which is defined as global search using only local search along with some memory for learning intermediate states as subgoals. Although it has not previously been studied in detail, this simple search framework with subgoal caching is fundamental to a variety of learning processes at an abstract level. For example, in terms of robot path planning [Latombe, 1991], it is a two-level planning scheme with subgoals being landmarks of either the workspace or configuration space. In terms of concept learning [Thornton, 1992], it corresponds to global concept approximation using only a locally-good extrapolator with subgoals as positive examples. In terms of case-based planning [Kolodner, 1993], it is having memory for cases and a local search for plan modifications and reuse. In terms of problem solving, the framework is simply to reduce new problems to previously solved ones using an existing resource-limited problem solver.

*This work has been performed at Sandia National Laboratories and supported by the U.S. Department of Energy under Contract DE-AC04-94AL85000.

In this paper, we present a bootstrap search algorithm, and develop some theory on its performance. Our presentation is in the context of problem solving. More concretely, we use the widely-studied 15-puzzle [Barr and Feigenbaum, 1981], the tile-sliding puzzle with 15 tiles on a 4 by 4 tray, as a motivating example. Thus, given the availability of a local search procedure (e.g., a search algorithm with some maximum time cutoff), we aim to study some ways of bootstrapping it into a global search using the memory of previously solved problems. Specifically, we characterize the effectiveness of the resulting global search and compare the relative capabilities. Further, if the local search is parameterized by some resource bound, we also provide a way of approximating the optimum resource bound so that an optimal local search may be used to yield the best global search.

Our work is similar to adaptive path planning [Chen, 1995; 1992], which studies the framework of improving an existing global path planner using a local path planner augmented with experience. The difference is that bootstrap search does not assume the availability of a pre-existing global searcher, which may be difficult to code or impractical to run. Hence, bootstrap search can be more widely applicable, although it will require more training in general to compensate for the lack of a teacher to provide solutions when local search fails.

Our work is superfacially related to hierarchical Q-learning [Kaelbling, 1993] in that we both use a landmark network; however, our emphasis is on deciding what goals to remember as subgoals rather than which local actions to take. Our work is also related to the use of abstraction and macro-operators [Korf, 1985b], which can be thought of as local methods. However, our emphasis is not on learning new macro-operators, but on improving the use of existing ones through new subgoals. In this respect, our work is similar to Stepping-Stone [Ruby and Kibler, 1989], which improves problem solving by learning new subgoal sequences. However, as in adaptive path planning, SteppingStone also relies on the availability of a global planner (brute-force search) to derive new subgoal sequences for a local planner (means-ends analysis) to follow. Moreover, SteppingStone uses general subgoals that represent subspaces of states. In contrast, we restrict our subgoals to specific states to

```
Algorithm Bootstrap(L)
  U ← {goal states};
  do forever
    v ← a problem instance;
    if (w ← L(v; U)) ≠ null then
      solve v by reducing it to w;
      if v ∉ U [and R(v) ⊈ R(U)] then
        insert v into U;      source(v) ← w;
```

Figure 1: Two simple but infeasible bootstrap search.

```
Algorithm Bootstrap(L, m)
  Maintain unbounded permanent memory U
  and working memory W with bounded size m.
  (U, W) ← (∅, {goal states});
  do forever
    v ← a problem instance;
    if (w ← L(v; (U, W))) ≠ null then
      solve v by reducing it to w;
      if w ∈ W then
        promote w from W to U;
        [maintain shortest path trees for U;]
      insert v into W;      source(v) ← w;
```

Figure 2: A more sophisticated bootstrap search.

gain simplicity. This simplicity allows us to develop a more rigorous understanding of the learning processes within the framework, and hopefully will provide further insight into others. Nevertheless, using specified states does have a more acute scalability problem because of the potentially large number of subgoals required.

2 Algorithm

The basic assumption in bootstrap search is that there is an efficient, though only locally effective search procedure, local, available that can transform (reduce) any state (problem) *u* to another *v* if the pair is 'near' by some metric. A greedy method is often sufficient to implement local. A problem *v* is directly solvable by local if *v* can be reduced to a goal state. To 'bootstrap' its global effectiveness, local is allowed to remember in memory *U* past problems that it had solved. These memory entries can be thought of as trail-markers in that each marker can be traced back to a goal state through calls of local. Of course, the more effective local is, the less bootstrapping it needs. The main issue of bootstrap search is how to selectively remember past solved problems so that future problems can still be efficiently solved.

To illustrate, consider the two simple but infeasible algorithms in Figure 1: the first one excludes the boxed fragment, and the second one includes it. We call the first .4(0), and the second .4(—1). In the algorithms, L is a procedure based on local augmented with memory *U.* Upon input problem v, *C* goes through *U* in some order, and returns the first solved problem *w* to which *v* can be reduced via local, if *w* exists; otherwise null is returned. To keep track of the solution paths, a back pointer source(v) for each trail-marker *v* is maintained.

In .4(0), the strategy is to store every solved problem in the past, excluding repetition. Obviously, this strategy will lead to memory explosion, let alone the utility problem [Minton, 1988] of eventual slowdown. Thus, one must stop the training of *A(0)* eventually and hope that it has received sufficient training. To curb the memory growth, A(—1) requires that the newly solved problem *v* contribute to the problem solving capability of current L. Given a problem x, let *R(x)* denote the set of problems reducible to *x* via local; for a set of problems *X,* let *R(X)* denote the union of *R(x)* over all x in A'. Then *A(—*1) requires that *R(v)* contain problems not in *R(U).* Although this requirement will decrease the redundancy within *U,* it nevertheless cannot be implemented in practice. Hence, we can only use A(-l) for theoretical comparisons.

We can be more sophisticated in our learning by augmenting *U* with a working set of trail-markers *W.* We can selectively remember useful markers by storing temporary markers in *W* and promoting them into permanent storage *U* only when they become useful. In Figure 2, we present *A(m),* the algorithm parameterized by m, the size of *W,* using this scheme. The boxed statement does not affect the problem solving capability of £ but should be included when solution quality is an issue.

In *A(m), C* checks first through *U* and then through *W* for the first solved problem *w* to which the new problem *v* can be reduced via local. If w; exists, it is returned; otherwise, null is returned. Thus, if *w* exists, *v* is solvable by *C* and is inserted into *W.* Learning occurs when *w E W,* i.e., when *v E R(W) \ R(U).* In this case, *w* is 'proven' useful and promoted into *U.* There is a forgetting process dictated by the finiteness of m, which determines the amount of reservoir for storing potentially useful entries. Because *v* has to be reducible to some current subgoal before it can be stored, the network of trail-markers is always connected. However, the training time required may be more than that of the alternative: Store new problems as potential subgoals even though they may not be currently solvable. This alternative, though, does have its problem of maintaining potentially disconnected network of subgoals.

In L's search through *U* and *W,* there may well be additional heuristics available for ordering the trail-markers for a potential match. Also, search time may be reduced by calling local only when the problem states are deemed sufficiently close by some heuristic measure. Further, portions of *U* may be skipped to foster more promotions from *W* and hence faster learning. However, to keep the algorithm simple and unbiased so that we may understand it more thoroughly, we employ no additional heuristics. We implement *U* with an unbounded first-in-first-access list and *W* with a rotating last-in-first-access list of size m. The stipulation on U allows us to derive the theoretical predictions later.

3 A Path Planning Example

Before applying our algorithm to the 15-puzzle, we first illustrate our algorithm with a simple robot path plan-

ning example. Consider a point robot operating in a 4-room workcell as shown in Figure 3a. The workcell is discretized at a resolution of 100 x 100; the center of the dividers is at (0,0); the lengths of both dividers are 80; and the initial robot 'home' position is at (10,10). Suppose that the only path planner available is local, which implements the simple 'go-straight' procedure so that it will succeed if and only if its two given points (starting and ending robot positions) are visible from each other. Using local, which is obviously not complete in this workcell, the robot is to go through a sequence of goal positions drawn uniformly at random. Thus, we need to increase the effectiveness of local.

Note that in adaptive path planning [Chen, 1995; 1992], we have the luxury of having a global searcher to provide a solution whenever the current network of subgoals is inadequate to produce one. In contrast, we do not have such a teacher in bootstrap search. Thus, we need to bootstrap ourselves by learning to achieve easy goals first and use these easy goals to achieve harder goals. Again, the main issue is which goals achieved should be remembered. We should also note that finding a path from the current robot position *s* to the goal position *t* is equivalent to finding a path from 'home' to the goal, because *s* is known to be connectable to 'home' through the current network of subgoals. Hence, we can view the path finding problem in the problem-reduction framework by identifying the 'home' position as the goal state, and the goal position as the problem state. Further, we may use whatever network learned to accomplish the task of connecting two arbitrary points by connecting them both to 'home' first. Thus, different goal states may be included in the problem-reduction framework by reducing the existing subgoals to the new goal state.

Using our algorithm, it is clearly possible to bootstrap local to total completeness because the workcell is connected under local. The deeper questions are how much training time and memory will be required. Shown in Figure 3b is the graph of the trail-markers learned by a random run of .4(0) until it becomes complete. Although in general we cannot know when completeness is reached, we can in this case by testing whether each of the four corners: .{(1,1), (-1,1), (-1,-1), (1,-1)}, are visible from a trail-marker. The figure shows that .4(0) required 21 markers, even at the benefit of knowing the optimal stopping time. In contrast, Figure 3c shows the sparsity of the graph learned by a random run of A(1). The number of markers is only one more than the theoretical minimum of 4. This 4-fold reduction in memory requirement is obtained at a price, though, of a 5-fold increase in training time: from 29 goals for .4(0) to 156 goals for *A(l).*

To study the algorithm more, we run *A(m)* 100 times each, for m = 0,1,2,4,8,16. We also consider different environment complexities by varying the lengths of the workcell dividers *d:* From *d* — 80 both, we decrease them both to *d* = 50, and increase them both to *d* = 90. The resulting average training time to completeness *T* and average size of memory at that time *S* are plotted in Figure 4. Clearly, for m > 0, the fast drop of *T* as *m*

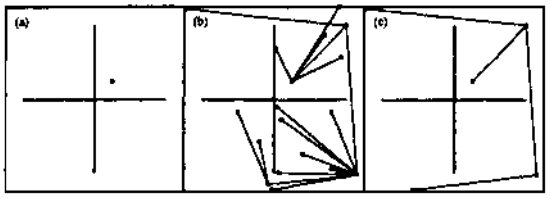


Figure 3: A 4-room workcell (a) with graphs of U from a random run of $\mathcal{A}(0)$ (b) and of $\mathcal{A}(1)$ (c).

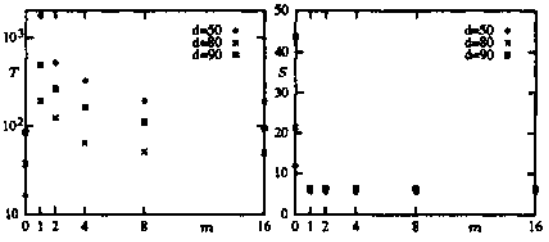


Figure 4: Average training time (T) and size (S) of permanent memory U versus working memory size m.

increases indicates that having sufficiently large reservoir of working memory (e.g., *m* > 8) is important in reducing the training time, but having more than the threshold will not yield much further reduction. Moreover, the lack of variation of *S* as m increases indicates that the size of working memory has little effect on the size of the final memory learned.

So far there are no surprises. However, as we compare the performance curves of *A* for different environments, we see an interesting phenomenon: *A* can actually require more training time in a seemingly easier environment. From the plot of T(m,d), we see that T(0,50) < T(0,80) < T(0,90), confirming the intuition that the shorter the dividers, the easier the environment is to learn. However, for *m* > 0, the plot actually shows on the contrary that T(m, 80) < T(m, 90) < T(m,50), suggesting that having local more powerful (wider doors implying more local successes) do not necessarily accelerate learning, but in fact can hamper learning. The reason for this behavior is due to the greedy nature of *A* in minimizing 5. The algorithm will promote a working marker to permanent storage only when it demonstrates usefulness. Therefore, when operating in an easy environment with *d* — 50, the algorithm can initially learn very quickly markers that will cover most of the workcell, leaving only a small region that is now unfortunately difficult to learn because goals in that small region will be needed to promote any working marker that is visible from it. For *d* = 80, the chance of such initial 'over-learning' is smaller because the doors are narrower. For *d* = 90, the chance of over-learning is even smaller; but because the doors are now much narrower, learning is significantly slowed. Therefore, as we increase the power of local (doorways widen), we will see the increase of both the chance of learning and the interplaying chance of over-learning.

4 Theory

In this section, we make some precise and strong statements about the performance of our algorithm through mathematical analysis; details of the proofs are provided in the appendix. We first give a sharp bound on the performance of A(0) in Theorem 1 by showing that the 'average' failure probability of C using its first k trail-markers decreases exponentially in k. Next, using .4(0) as a reference, we show that the performance of .4(1) is better than that of A(-l), which is better than that of .4(0). The comparison is based on the 'average' failure probability (or 'average utility' in reverse order) of C using the first k markers of each algorithm for each k. Finally, we present an upper bound on the 'average' search cost of A(m) for all m in Theorem 3. From this theorem, a technique for finding the best resource bound c on local(c) is developed in Section 5.

As in the framework of PAC-learning [Natarajan, 1991], we assume that the problems are randomly drawn from a fixed distribution — in fact, we shall assume a uniform distribution for simplicity. To facilitate our discussion, we use subscript n on a program variable to denote its value at the n^{th} loop, and parameter m to indicate its correspondence to A(m). Additionally, for ib > 0, let u_k be the kth entry to be inserted into memory U. Thus, $R(U_n\{m\})$ denotes the set of problems reducible to any of the previously solved and stored problems in U after A(m) is trained with n problems. The following random variables (with parameter m omitted for notational simplicity) are important in characterizing the learning process.

A_n	The failure probability of $\mathcal{A}$ using U_n alone, i.e., the probability that a random problem x does not belong to $R(U_n)$, or equivalently, one minus the probability mass on $R(U_n)$.
I_n	The 0-1 variable indicating the promotion of w_{n+1} from W to U on the chance that $w_{n+1} \in R(w_{n+1}) \setminus R(U_n)$, i.e., $\lceil w_{n+1} \in W_n \rfloor$, where $\lceil \cdot \rfloor$ is the indicator function.
L_n	The amount of additional learning achieved by remembering w_{n+1} conditional on $I_n = 1$, i.e., the probability of a random problem x belonging to $R(U_{n+1})$ but not $R(U_n)$, or equivalently, the probability mass on $R(U_{n+1}) \setminus R(U_n)$.

Notice the fundamental equation of $A_{n+1} = A_n - L_n I_n$, regardless of m. To study the utility of U, we use index (k) with $(0) = 0$ to denote the k^{th} $n > 0$ such that $I_n = 1$, if it exists; otherwise infinity. Thus, $A_{(0)} = 1$, $A_{(k+1)} = A_{(k)+1}$, and $A_{(k)}$ is the failure probability right before the insertion of u_{k+1}. Moreover, we have $A_{(k+1)} = A_{(k)} - L_{(k)}$ with $L_\infty \stackrel{def}{=} 0$. Now we introduce a randomized problem model motivated by the 15-puzzle, and study the consequences of this equation under the model.

Definition 1 Let local(c) be a local search procedure with maximum search cost c. A random uniform digraph of problems with edge probability function F(c) is a set of uniformly distributed problems in which every problem using local(c) is independently solvable and reducible to every other problem with probability F(c).

Thus, the probability that local(∞) will yield a solution with search cost no greater than c is F(c).

Theorem 1 The average failure probabilities of A(0) when applied on a random uniform digraph of problems of size N decreases almost geometrically in that for all k,

$$(1-F(c))^k \le \mathbf{E}A_{(k)}(0) \le (1-F(c))^k + (1-F(c))^N. \quad (1)$$

With the performance of .4(0) as a reference, the following theorem shows that the utility of memory U(l) is higher than that of U(-1), which is in turn higher than that of U(0). In other words, .4(1) is better than A(-l) which is better than .4(0) in that A(1) will tend to remember a more 'compact' set of intermediate solutions than A(-l), similarly for .4(0).

Theorem 2 The average failure probabilities of A{\), A(0) and A(—1) when applied on a random uniform digraph of problems satisfy

$$\begin{aligned} \mathbf{E}\Pr(A_{(k)}(1) \le a) &\ge \mathbf{E}\Pr(A_{(k)}(-1) \le a) \\ &\ge \mathbf{E}\Pr(A_{(k)}(0) \le a). \end{aligned} \quad (2)$$

for all k. Consequently, the average failure probabilities of the first k memory entries of the algorithms satisfy

$$\mathbf{E}A_{(k)}(1) \le \mathbf{E}A_{(k)}(-1) \le \mathbf{E}A_{(k)}(0). \quad (3)$$

Although the preceding theorem is a strong statement about the relative performance of A(1), A(0), and A(-l), nothing similar is known about A(m) for m ≥ 2. We conjecture that $\mathcal{A}(m)$ for $m > 2$ is also better than A(0) in that $\mathbf{E}A_{(k)}(m) \le \mathbf{E}A_{(k)}(0)$. The following theorem, however, does address the search cost of A(m) for general m.

Theorem 3 For arbitrary m, suppose that we apply A(m) with local(c) on a random uniform digraph of problems, and that local(c) has conditional expected search cost $\gamma_0(c)$ upon success. Then the expected search cost of A(m) per problem is

$$\gamma(c) \le c(1/F(c) - 1) + \gamma_0(c). \quad (4)$$

Further, suppose that $\mathcal{A}(m)$ has failure probability a after certain amount of training, and that local(∞) *has weighted cost $\gamma_1(a) = \int_0^{F^{-1}(a)} z\,dF(z)$ for the lower a-quantile. Then for the next problem, the expected search cost of $\mathcal{A}(m)$ backed up by* local(∞) *is*

$$\bar{\gamma}(c) \le \gamma(c) + \gamma_0(\infty) - \gamma_1(1-a). \quad (5)$$

5 Application to the 15-Puzzle

To demonstrate, we apply our algorithm and theory to the 15-puzzle. Here, the object is to be able to solve all 16!/2 solvable configurations, though not necessarily in the shortest number of moves. There are of course many different ways of solving the puzzle [Korf, 1985b; Poiitowski, 1986; Ratner and Pohl, 1986; Ruby and Kibler, 1989]. Since bootstrap search is a weak method, we do not expect it to perform better than other methods that take advantage of additional knowledge. Rather, we

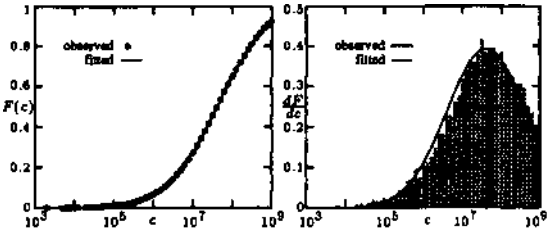


Figure 5: Approximation of $F(c)$ and its density under log scale on c.

use the puzzle to demonstrate the generic applicability of bootstrap search when nothing else is available.

Thus, suppose that we have available only a subroutine local(c), which implements iterative-deepening with Manhatten distance heuristic [Korf, 1985a] and maximum search cost c, measuring the number of nodes generated. We ask the question, "Is it possible to bootstrap local(c) (with unlimited amount of training) so that the average search cost is less than that of simply applying local(∞)?" We also ask, "Is it possible to only bootstrap local(c) to a certain degree of capability and back it up with local(∞), so that the average total search cost is less than that of simply applying local(∞)?" As we shall see, the answer to both questions is yes with roughly two orders of magnitude improvement. However, *c* must be sufficiently large for both cases, and cannot be too large (depending on the desired capability) for the second case. To reach this conclusion, we first need to justify the random digraph model and study *F(c)*.

Obviously, the digraph of the solvable states of the 15-puzzle induced by local(c) is not random. However, the number of states *N* = 161/2 is extremely large and the digraph is almost regular. Hence, it is plausible to model the digraph of the 15-puzzle by the random digraph with *F(c)* being the fraction of states solvable by local(c). To study this fraction, we apply local(109) to 10000 randomly generated solvable states, and record the fraction of successes with search cost less than or equal to c, against case increases to 109. Since brute-force search costs tend to be exponential, we use log scale on c. We plot log c against the fraction of success under local(c) to obtain the cumulative distribution function and the density histogram in Figure 5. The figure shows that the distribution is in fact approximately lognormal. Using the quantile estimators [Aitchison and Brown, 1957] (27–73% for μ; 8–92% for σ), we estimate that $F(c) = \Lambda(c \mid \mu, \sigma)$, with $\mu \doteq 17.536$ and $\sigma \doteq 2.3436$, where Λ denotes the two-parameter lognormal distribution. Thus, let $x = \log c$ and $\tilde{x} = (\ln c - \mu)/\sigma = (x \ln 10 - \mu)/\sigma$. Then

$$F(c) = P(\tilde{x}) \stackrel{\text{def}}{=} \frac{1}{2\pi} \int_{-\infty}^{\tilde{x}} e^{-t^2/2}\, dt$$

is the Normal probability function.

Having approximated F(c), we next describe our bootstrap search experiment and verify our theoretical predictions before answering the questions posed in the beginning of this section. For each x = 5,6,7,8, we compare .4(1) and .4(20) by running them on 10000 random

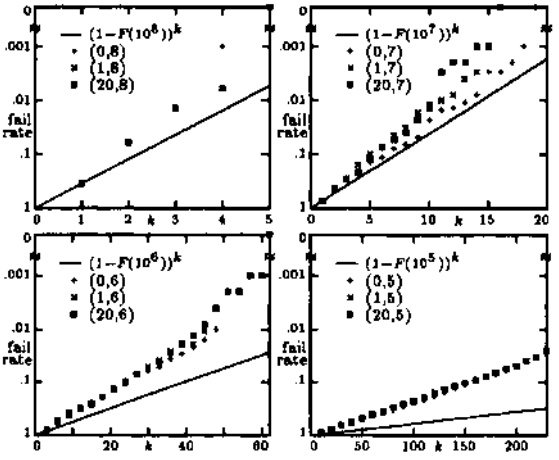
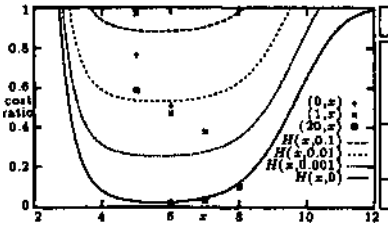


Figure 6: Failure rates of first k entries on logscale.

problems. For reference, we also run .4(0), but with a pre-chosen bound *b* on the memory storage: *b* = 20 for both x = 7,8; 6 = 50 for x = 6; 6 = 200 for x = 5. These bounds are chosen so that storage requirements are comparable to that of .4(1) and A(20). For each x, we denote the data corresponding to .4(0), .4(1), .4(20) as type (0,x), (I,x), (20,x), respectively. For all three algorithms, we use the last 1000 random problems to measure their properties at the end of the 9000 training problems.

One property is the utility of the permanent trail-markers learned. We tabulate the number of problems that require *k* memory accesses, and estimate *A(k)* by the fraction of problems unsolvable with the first *k* markers. To allow a closer look at the failure probabilities for large *k,* we plot the negative log of the failure frequencies in Figure 6, with reference line k log(I — *P(x))* anticipated by Theorem 1. For each algorithm, the data for *k* up to the size of the permanent memory is plotted. Several observations can be made from this figure. First, the reference lines do not approximate the (0, x) data very well, but do support all data from below. The bad approximation may be explained by the fact that the state space of the 15-puzzle is really not a random graph, but only an approximately regular graph. However, the appearance of the reference lines supporting the data from below provide evidence that the algorithms do perform more successfully than predicted under the idealized random-graph model. Another observation is that as x decreases, .4(1) becomes less trained than A(20). Simultaneously, the relative size of *U(1)* to that of U(20) also decreases, as indicated by the largest *k* attained for each data set. Obviously, as the power of local decreases (x decreases), the more working markers is needed for faster bootstrapping. With just one working marker, A(1) cannot learn as quickly as .4(20) with the same number of training problems. Finally, we can clearly see the higher memory utility of A(1) compared to that of A(0), as predicted by Theorem 2. The data of type (I,x) is generally higher



type	a
(0,5)	0.049
(1,5)	0.296
(20,5)	0.016
(0,6)	0.009
(1,6)	0.007
(1,7)	0.003

Figure 7: Cost ratios of *A(m)* backed up by local(oo) to local(oo) alone.

than that of type (0,x). Although we do not see such generality between data of types (1, *x)* and (20, *x*), we do also see that data of type (20, *x)* is generally higher than that of type of (0, *x)*. These data support our conjecture that $\mathbf{E}A_{(k)}(m) \leq \mathbf{E}A_{(k)}(0)$ for arbitrary m.

Finally, we measure the average search cost of each algorithm backed up by local(∞) and compare that with the theoretical predictions of Theorem 3. By straightforward computation, we have

$$\gamma_0(c) = \int_0^c z\, dF(z)/F(c) = e^{\mu+\sigma^2/2} P(\tilde{x}-\sigma)/P(\tilde{x}), \quad (6)$$

where $e^{\mu+\sigma^2/2} \doteq 6.43 \times 10^8$ is the theoretical average cost of local(∞). Similarly,

$$\gamma_1(a) = \int_0^{F^{-1}(a)} z\, dF(z) = e^{\mu+\sigma^2/2} P(P^{-1}(a)-\sigma), \quad (7)$$

giving us the upper bound of

$$H(x,a) \stackrel{\text{def}}{=} e^{\sigma\tilde{x}-\sigma^2/2}(1/P(\tilde{x})-1) + P(\tilde{x}-\sigma)/P(\tilde{x}) + 1 - P(P^{-1}(1-a)-\sigma)$$

for the ratio of the average search cost of *A(m)* backed up by local(∞) to that of local(∞) one. We plot the theoretical upper bound for *a* = 0.1,0.01,0.001,0, and the observed data points in Figure 7. The data points with observed failure probability *a* > 0 are listed in the adjacent table. Careful checking shows that the observed data points are indeed consistently lower than the predicted upper bound. Taking the failure probabilities into consideration, we see that A(20) with local(10^6) is the best of the 12 algorithms compared, yielding the lowest search cost ratio of 0.0159.

Now suppose that the upper bounds are indeed true. Then from *H(x,* 0), we see that after *A(m)* becomes fully trained (i.e., without the need of local(∞) as a backup), it can search with average cost less than that of local(∞) as long as *x* > 3, or c > 1000. However, from *H(x, a)* for *a* > 0, we see that if *A(m)* is not fully trained, then the range of *x* for which *A(m)* (with local(∞) as a backup) can search with average cost less than of local(oo) alone necessarily has an upper bound. For example, if *a* = 0.1, then *x* must be greater than 3.8 and less than 8.2. This 'over-learning' phenomenon of powerful local search becoming detrimental can be explained: If a > 0, then there may be problems more difficult than *A(m)* can handle; in this case, fruitless search will be incurred by *A(m),* causing local(∞) alone to be better.

6 Conclusion

We have presented an algorithm for bootstrap search, and provided some initial theory on their performance. Our theoretical analysis is based on a problem model of a random digraph. Using this model, we have made some strong performance predictions and comparisons of the algorithm. Further, we have illustrated some techniques for locating the optimal 'power' of the local search to be bootstrapped so as to yield the best global search. We have empirically evaluated our algorithm by applying it to both the 15-puzzle and a simple robot path planning problem. In both domains, we have 1) explained the observed performance behavior in terms of the theory developed; 2) explored the importance of having sufficiently large set of working trail-markers; and 3) identified a common detrimental phenomenon of over-learning when local search becomes too powerful. Incidentally, we have also contributed some new results on solving the 15-puzzle. In particular, we have made a natural but not widely recognized connection between search costs and the lognormal distribution.

Our work is by no means complete. Theoretically, we have not addressed the issue of training time, nor the issue of solution quality. Within the random digraph model, there are conjectures yet to be settled. Outside the random digraph model, there are plenty of other problem models that may yield further insights into the area of bootstrap search. In particular, the path planning problem addressed in this paper should provide motivation for a different model suitable for analysis. There may also be some other bootstrapping algorithms waiting to be discovered. With its broad applicability in search and learning, further research is definitely needed.

A Proofs

Proof (Theorem 1) Since only $\mathcal{A}(0)$ is involved and c is constant, we drop parameter (0) and let $F(c) = 1-\alpha = \bar{\alpha}$ for notational simplicity. We first evaluate $\mathbf{E}(L_{(k)} \mid A_{(k)})$. If $R(U_{(k)}) \setminus U_{(k)} \neq \emptyset$, then u_{k+1} can be found and whatever problems not in $R(U_{(k)})$ will be reducible to u_{k+1} with independent probability $\bar{\alpha}$. However, if $R(U_{(k)}) \setminus U_{(k)}$ is in fact empty, then $(k) = \infty$ and $L_{(k)} = 0$. This event can occur for $k > 0$ and with probability at most $\alpha^{(N-k+1)k}$ when all $N-k+1$ problems outside $U_{(k)}$ are not reducible to $U_{(k)}$. (The first trail-marker that records the goal states is not considered part of the N problems.) Hence,

$$\bar{\alpha}A_{(k)} \geq \mathbf{E}(L_{(k)} \mid A_{(k)}) \geq \bar{\alpha}A_{(k)}(1-\alpha^{(N-k+1)k}). \quad (8)$$

Consequently, from $\mathbf{E}A_{(k+1)} = \mathbf{E}\mathbf{E}(A_{(k+1)} \mid A_{(k)}) = \mathbf{E}A_{(k)} - \mathbf{E}(L_{(k)} \mid A_{(k)})$, we have

$$\alpha\mathbf{E}A_{(k)} \leq \mathbf{E}A_{(k+1)} \leq \alpha\mathbf{E}A_{(k)} + \bar{\alpha}\alpha^{(N-k+1)k} \quad (9)$$

implying

$$\alpha^{k+1} \leq \mathbf{E}A_{(k+1)} \quad (10)$$

$$\leq \alpha^{k+1} + \bar{\alpha} \sum_{0<j\leq k} \alpha^{(N-j+1)j+k-j} \quad (11)$$

$$\leq \alpha^{k+1} + \alpha^N \bar{\alpha} \sum_{j\geq 0} \alpha^j, \quad (12)$$

which yields the desired result. ∎

Proof (Theorem 2) (Sketch) Let the problem set be of finite size N; for infinite set, simply take the appropriate limits. Let $0 \le a, b \le 1$ be integral multiples of $1/N$. The proof of (2) is by induction on k; the base case of $k = 0$ is trivial. Given a particular digraph, we have

$$\Pr(A_{(k+1)}(m) \le b) =$$

$$\sum_a \Pr(A_{(k)}(m) = a) \Pr(L_{(k)}(m) \ge a - b \mid A_{(k)}(m) = a)$$

as a result of $A_{(k+1)}(m) = A_{(k)}(m) - L_{(k)}(m)$. Averaging over the digraphs and using the fact that the problems are uniformly distributed, we have

$$\mathbf{E}\Pr(A_{(k+1)}(m) \le b) = \sum_a \mathbf{E}\Pr(A_{(k)}(m) = a) P_L(k, m, a, b), \quad (13)$$

where $P_L(k, m, a, b)$ denotes the conditional average of $\Pr(L_{(k)}(m) \ge a - b)$ given that $R(U_{(k)}(m))$ is some particular problem set X of size $N(1-a)$. We now use two properties of P_L whose proofs are more involved and are omitted:

$$P_L(k, 1, a, b) \ge P_L(k, -1, a, b) \ge P_L(k, 0, a, b); \quad (14)$$

$$P_L(k, -1, a, b) \ge P_L(k, -1, a + 1/N, b). \quad (15)$$

From (14), we have

$$\mathbf{E}\Pr(A_{(k+1)}(1) \le b) \ge \sum_a \mathbf{E}\Pr(A_{(k)}(1) = a) P_L(k, -1, a, b) \quad (16)$$

$$= \sum_a \mathbf{E}\Pr(A_{(k)}(1) \le a) \Delta P_L(k, -1, a, b) \quad (17)$$

where $\Delta P_L(k, -1, a, b) = P_L(k, -1, a, b) - P_L(k, -1, a + 1/N, b)$ is nonnegative from (15). Hence, by induction, we have

$$\mathbf{E}\Pr(A_{(k+1)}(1) \le b) \ge \sum_a \mathbf{E}\Pr(A_{(k)}(-1) \le a) \Delta P_L(k, -1, a, b) \quad (18)$$

$$= \sum_a \mathbf{E}\Pr(A_{(k)}(-1) = a) P_L(k, -1, a, b) \quad (19)$$

$$= \mathbf{E}\Pr(A_{(k+1)}(-1) \le b). \quad (20)$$

The induction step of showing

$$\mathbf{E}\Pr(A_{(k+1)}(0) \le b) \le \mathbf{E}\Pr(A_{(k+1)}(1) \le b)$$

is done similarly. Finally, (3) follows directly from (2) and the fact that $N\mathbf{E}A_{(k)}(m) = \sum_a \mathbf{E}\Pr(A_{(k)}(m) > a) = \sum_a (1 - \mathbf{E}\Pr(A_{(k)}(m) \le a))$. ∎

Proof (Theorem 3) Let $U[k]$ be the first k marker to be accessed. Let x be some problem, and κ be the expected number of memory accesses before solving x or exhausting all available markers. Then

$$\kappa \le \mathbf{E} \sum_{k \ge 0} (k+1) \lceil x \in R(U[k+1]) \setminus R(U[k]) \rceil. \quad (21)$$

If the $(k+1)^{th}$ entry exists and x is not in $U[k+1]$, then x will be in $R(U[k+1]) \setminus R(U[k])$ with probability $F(c)(1 - F(c))^k$; otherwise, x will not. Consequently, $\kappa \le \sum_{k \ge 0} (k+1) F(c)(1 - F(c))^k = 1/F(c)$. Thus, $\gamma(c) \le c(\kappa - 1) + \gamma_0(c)$ yields (4). If $\mathcal{A}(m)$ is backed up by local(∞), then the expected cost to be incurred by local(∞) can be at most the weighted cost of the most costly problems whose probability is a. Thus, $\tilde{\gamma}(c) \le \gamma(c) + \int_{F^{-1}(1-a)}^{\infty} z \, dF(z) = \gamma(c) + \gamma_0(\infty) - \gamma_1(1-a)$. ∎

References

[Aitchison and Brown, 1957] J. Aitchison and J. Brown. The Lognormal Distribution. Cambridge University Press, 1957.

[Barr and Feigenbaum, 1981] A. Barr and E. Feigenbaum. The Handbook of Artificial Intelligence, v. 1, William Kaufmann, Inc., 1981.

[Chen, 1992] P. Chen. Improving Path Planning with Learning. Machine Learning: Proc. of the Ninth Int. Conf, pp. 55-61, 1992.

[Chen, 1995] P. Chen. Adaptive Path Planning: Algorithm and Analysis. IEEE Int. Conf. on Robotics and Automation, 1995.

[Kaelbling, 1993] L. Kaelbling. Learning to Achieve Goals. Proc. of the 13th IJCAI, pp. 1094-1098, 1993.

[Kolodner, 1993] J. Kolodner. Case-Based Reasoning, Morgan Kaufmann Publishers, 1993.

[Korf, 1985a] R. Korf. Depth-First Iterative-Deepening: An Optimal Admissible Tree Search. Artificial Intelligence, 27, pp. 97-109, 1985.

[Korf, 1985b] R. Korf. Learning to Solve Problems by Searching for Macro-Operators, Pitman Advanced Publishing Program, 1985.

[Latombe, 1991] J.-C. Latombe. Robot Motion Planning, Kluwer Academic Publishers, 1991.

[Marshall and Olkin, 1979] A. Marshall and I. Olkin. Inequalities: Theory of Majorization and Its Applications, Academic Press, 1979.

[Minton, 1988] S. Minton. Learning Search Control Knowledge: An Explanation-based Approach, Kluwer Academic Publishers, 1988.

[Natarajan, 1991] B. Natarajan. Machine Learning: A Theoretical Approach, Morgan Kaufmann, 1991.

[Politowski, 1986] G. Politowski. On construction of Heuristic Functions, PhD thesis, UC Santa Cruz, 1986.

[Ratner and Pohl, 1986] D. Ratner and I. Pohl. Joint and LPA*: Combination of Approximation and Search. Proc. of the AAAI, pp. 173-177, 1986.

[Ruby and Kibler, 1989] D. Ruby and D. Kibler. Learning Subgoal Sequences for Planning. Proc. of the Eleventh IJCAI, pp. 609-614, 1989.

[Thornton, 1992] C. Thornton. Techniques in Computational Learning, Chapman & Hall Computing, 1992.