## CS-171, Intro to A.I. — Final Exam — Fall Quarter, 2013

NAME AND EMAIL AI	DDRESS:		
Your ID:	ID TO RIGHT:	ROW:	NO. FROM RIGHT:

The exam will begin on the next page. Please, do not turn the page until told.

When you are told to begin the exam, please check first to make sure that you have all 10 pages, as numbered 1-10 in the bottom-left corner of each page.

The exam is closed-notes, closed-book. No calculators, cell phones, electronics.

Please clear your desk entirely, except for pen, pencil, eraser, an optional blank piece of paper (for optional scratch pad use), and an optional water bottle. Please turn off all cell phones now.

This page summarizes the points available for each question so you can plan your time.

- 1. (15 pts total, 5 pts each, -1 each error, but not negative) Bayesian Networks.
- 2. (10 pts total, -1 for each error, but not negative) Mini-Max, Alpha-Beta Pruning.
- 3. (10 pts total, -2 for each error, but not negative) Conversion to CNF.
- 4. (10 points total, 2 pts each) Constraint Satisfaction Problems.
- 5. (5 pts total, -1 for each error, but not negative) Constraint Graph.
- 6. (5 pts total, -2 for each error, but not negative) k-Nearest-Neighbor Classifier.
- 7. (10 pts total, 2 pts each) Search.
- 8. (10 pts total) Decision Tree Classifier Learning.
- 9. (5 pts total, -1 pt each wrong answer, but not negative) Search Properties.
- 10. (10 pts total, -2 for each error, but not negative) Resolution Theorem Proving.
- 11. (10 pts total, 2 pts each) FOPC Knowledge Engineering In The Blocks World.

The Exam is printed on both sides to save trees! Work both sides of each page!

#### 1. (15 pts total, 5 pts each, -1 each error, but not negative) Bayesian Networks.

**1a. (5 pts)** Write down the factored conditional probability expression that corresponds to the graphical Bayesian Network shown.



**1b. (5 pts)** Draw the Bayesian Network that corresponds to this conditional probability: P(A | B,C,E) P(B | D,G) P(C | E,F,H) P(D | G) P(E| G,H) P(F | I) P(G | H) P(H | I) P(I)

**1.c. (5 pts)** Shown below is the Bayesian network corresponding to the Burglar Alarm problem, P(J | A) P(M | A) P(A | B, E) P(B) P(E).



The probability tables show the probability that variable is True, e.g., P(M) means P(M=t). Write down an expression that will evaluate to  $P(j=f \land m=t \land a=t \land b=t \land e=f)$ . Express your answer as a series of numbers (numerical probabilities) separated by multiplication symbols. You do not need to carry out the multiplication to produce a single number (probability). **SHOW YOUR WORK.** 

$$P(j=f \land m=t \land a=t \land b=t \land e=f)$$

=

2. (10 pts total, -1 for each error, but not negative) Mini-Max, Alpha-Beta Pruning.

In the game tree below it is **Max**'s turn to move. At each leaf node is the estimated score of that resulting position as returned by the heuristic static evaluator.

(1) Perform Mini-Max search and label each branch node with its value.

(2) Cross out each leaf node that would be pruned by alpha-beta pruning.

(3) What is Max's best move (A, B, or C)?



3. (10 pts total, -2 for each error, but not negative) Conversion to CNF. Convert this Propositional Logic wff (well-formed formula) to Conjunctive Normal Form and simplify. Show your work (correct result, 0 pts; correct work, 5 pts).

 $[\neg (Q \Leftrightarrow P)] \Rightarrow Q$ 

4. (10 points total, 2 pts each) Constraint Satisfaction Problems. See Chapter 6.



You are a map-coloring robot assigned to color this South-East Asia map. Adjacent regions must be colored a different color (R=Red, B=Blue, G=Green). The constraint graph is shown.

#### 4a. (2pts total, -1 each wrong answer, but not negative) FORWARD CHECKING.

Cross out all values that would be eliminated by Forward Checking, after variable KA has just been assigned value R as shown:

KA	LA	MA	MY	TH	VI
R	R G B	R G B	R G B	R G B	R G B

## 4b. (2pts total, -1 each wrong answer, but not negative) ARC CONSISTENCY.

KA and TH have been assigned values, but no constraint propagation has been done. Cross out all values that would be eliminated by Arc Consistency (AC-3 in your book).

KA	LA	MA	MY	TĤ	VI
R	RGB	RGB	RGB	G	RGB

# **4c. (2pts total, -1 each wrong answer, but not negative) MINIMUM-REMAINING-VALUES HEURISTIC.** Consider the assignment below. TH is assigned and constraint propagation has been done. List all unassigned variables that might be selected by the Minimum-Remaining-Values (MRV) Heuristic: \_\_\_\_\_\_.

KA	LA	MA	MY	TH	VI
G B	GΒ	GΒ	GΒ	R	RGB

## 4d. (2pts total, -1 each wrong answer, but not negative) DEGREE HEURISTIC.

Consider the assignment below. (It is the same assignment as in problem 4c above.) TH is assigned and constraint propagation has been done. List all unassigned variables that might be selected by the Degree Heuristic:

KA	LA	MA	MY	TH	VI
G B	G B	GΒ	G B	R	RGB

**4e. (2pts total) MIN-CONFLICTS HEURISTIC.** Consider the complete but inconsistent assignment below. LA has just been selected to be assigned a new value during local search for a complete and consistent assignment. What new value would be chosen below for LA by the Min-Conflicts Heuristic?.

KA	LA	MA	MY	TH	VI
В	?	R	G	G	В

#### 5. (5 pts total, -1 for each error, but not negative) Constraint Graph.

You are a map-coloring robot assigned to color this South America map. Adjacent regions must be colored a different color. Draw the constraint graph corresponding to the map.



### 6. (5 pts total, -2 for each error, but not negative) k-Nearest-Neighbor Classifier.

You have trained a k-Nearest Neighbor classifier on the points shown below, which are labeled as either Black (B) or White (W). What will the classifier return as the class for the point X, shown as a star, in the following scenarios? Answers should be Black (B), White (W), or Tie (T).



7. (10 pts total, 2 pts each) Execute Tree Search through this graph (i.e., do not remember visited nodes). Step costs are given next to each arc. Heuristic values are next to each node (as h=x). The successors of each node are indicated by the arrows out of that node. Successors are returned in left-to-right order.

For each search strategy, show the order in which nodes are expanded (i.e., to expand a node means that its children are generated), ending with the goal node that is found. Show the path from start to goal, or write "None". Give the cost of the path found. The first one is done for you as an example.



**8. (10 pts total) Decision Tree Classifier Learning.** You are a robot in a lumber yard, and must learn to discriminate Oak wood from Pine wood. You choose to learn a Decision Tree classifier. You are given the following examples:

Example	Density	Grain	Hardness	Class
Example #1	Light	Small	Hard	Oak
Example #2	Heavy	Large	Hard	Oak
Example #3	Light	Large	Hard	Oak
Example #4	Heavy	Small	Medium	Oak
Example #5	Light	Small	Medium	Pine
Example #6	Heavy	Large	Soft	Pine
Example #7	Light	Large	Soft	Pine
Example #8	Heavy	Small	Soft	Pine

8a. (2 pts) Which attribute would information gain choose as the root of the tree?

\_\_\_\_\_<u>.</u>

**8b. (4 pts)** Draw the decision tree that would be constructed by recursively applying information gain to select roots of sub-trees, as in the Decision-Tree-Learning algorithm.

Classify these new examples as Oak or Pine using your decision tree above. **8c. (2 pts)** What class is [Density=Light, Grain=Small, Hardness=Soft]? \_\_\_\_\_ **8d. (2 pts)** What class is [Density=Heavy, Grain=Large, Hardness=Medium]? \_\_\_\_

## 9. (5 pts total, -1 pt each wrong answer, but not negative) Search Properties.

Fill in the values of the four evaluation criteria for each search strategy shown. Assume a tree search where b is the finite branching factor; d is the depth to the shallowest goal node; m is the maximum depth of the search tree; C<sup>\*</sup> is the cost of the optimal solution; step costs are identical and equal to some positive  $\varepsilon$ ; and in Bidirectional search both directions use breadth-first search.

Note that these conditions satisfy all of the footholes of Fig. 3.21 in your bo				
Criterion	Complete?	Time complexity	Space complexity	Optimal?
Breadth-First				
Uniform-Cost				
Depth-First				
Iterative Deepening				
Bidirectional				
(if applicable)				

Note that these conditions satisfy all of the footnotes of Fig. 3.21 in your book.

**10. (10 pts total, -2 for each error, but not negative) Resolution Theorem Proving.** You are a robot in a logic-based question answering system, and must decide whether or not an input goal sentence is entailed by your Knowledge Base (KB). Your current KB in CNF is:

S1: (PQ) S2: (¬PQ) S3: (P¬Q) S4: (¬P¬Q¬S) S5: (¬PRS)

Your input goal sentence is: (  $P \land Q \land R$ ).

10a. (2 pts) Write the negated goal sentence in CNF.

S6:\_\_\_\_\_

**10b. (8 pts total, -2 for each error, but not negative)** Use resolution to prove that the goal sentence is entailed by KB, or else explain why no such proof is possible. For each step of the proof, fill in Si and Sj with the sentence numbers of previous CNF sentences that resolve to produce the CNF result that you write in the resolvent blank. The resolvent is the result of resolving the two sentences Si and Sj. Use as many steps as necessary, ending by producing the empty clause. The shortest proof I know of is only six lines long.

Resolve Si	with Sj	to produce resolvent S7:
Resolve Si	with Sj	to produce resolvent <b>S8:</b>
Resolve Si	with Sj	to produce resolvent <b>S9</b> :
Resolve Si	with Sj	to produce resolvent S10:
Resolve Si	with Sj	to produce resolvent S11:
Resolve Si	with Sj	to produce resolvent S12:
Resolve Si	with Sj	to produce resolvent S13:
Resolve Si	with Sj	to produce resolvent S14:
Resolve Si	with Sj	to produce resolvent S15:

#### 11. (10 pts total, 2 pts each) FOPC KNOWLEDGE ENGINEERING IN THE BLOCKS WORLD.

You are a Knowledge Engineer assigned to the Blocks World, which involves controlling a robot arm that stacks children's blocks one atop another, or on a table, into a desired configuration. For example, you are concerned with configurations such as:



Here we wish only to describe static (unmoving) configurations that will become goals (targets) in the Blocks World. A separate module, not your concern, will move the robot arm to achieve these goals. You need only to describe correctly in FOPC the static goal (target) configurations.

Write the FOPC sentence that best represents the corresponding English sentence. <u>Assume that all objects in the world are blocks</u>, i.e., there is no need for Block(x) guard predicates. Use "Stacked(x, y)" to mean that "Block x is stacked directly on top of block y."

The first one is done for you as an example.

**11.a.** Assert that "Block x is stacked on block y" implies "Block y is not stacked on block x."

 $\forall x, y \text{ Stacked}(x, y) \Rightarrow \neg \text{Stacked}(y, x)$ 

**11.b.** (**2pts**) Define a predicate "Clear(x)" to mean that no block y is stacked on block x.

 $\forall x, y \operatorname{Clear}(x) \Leftrightarrow$ 

**11.c.** (2pts) Define a predicate "OnTable(x)" to mean that block x is on the table, i.e., not on any block.

 $\forall x, y \text{ OnTable}(x) \Leftrightarrow$ 

**11.d.** (**2pts**) Define a predicate "Above(x, y)" to mean that x is above y in a stack including both x and y.

 $\forall x, y \text{ Above}(x, y) \Leftrightarrow$ 

**11.e.** (**2pts**) State that at least one block must have no other block stacked upon it. You may use the Clear(x) predicate that you defined in (10.b) above

**11.f.** State that at least one block must be on the table. You may use the OnTable(x) predicate that you defined in (10.c) above

### \*\*\*\* THIS IS THE END OF THE FINAL EXAM \*\*\*\*