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| Autore | Dosi, Gianfranco |
| Titolo | L'avvocato del minore nei procedimenti civili e penali / Gianfranco Dosi |
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| Soggetti | Minori - Diritti<br>Avvocati penalisti<br>Difensori |
| Lingua di pubblicazione | Italiano |
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| Livello bibliografico | Monografia |
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| Record Nr. | UNINA9910783135503321 |
| Autore | Ghallab Malik |
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| Pubbl/distr/stampa | Amsterdam ; ; Boston, : Elsevier/Morgan Kaufmann, c2004 |
| ISBN | 9780080490519 (Electronic Book) |
| Descrizione fisica | 1 online resource (664 p.) |
| Collana | The Morgan Kaufmann Series in Artificial Intelligence |
| Altri autori (Persone) | NauDana S<br>TraversoPaolo |
| Disciplina | 658.5 |
| Soggetti | Production planning - Data processing |
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| Nota di bibliografia | Includes bibliographical references (p. 573-607) and index. |
| Nota di contenuto | Front Cover; Automated Planning Theory and Practice; Copyright Page; Contents; About the Authors; Foreword; Preface; Table of Notation; Chapter 1. Introduction and Overview; 1.1 First Intuitions on Planning; 1.2 Forms of Planning; 1.3 Domain-Independent Planning; 1.4 Conceptual Model for Planning; 1.5 Restricted Model; 1.6 Extended Models; 1.7 A Running Example: Dock-Worker Robots; Part I: Classical Planning; Chapter 2. Representations for Classical Planning; 2.1 Introduction; 2.2 Set-Theoretic Representation; 2.3 Classical Representation; 2.4 Extending the Classical Representation<br>2.5 State-Variable Representation2.6 Comparisons; 2.7 Discussion and Historical Remarks; 2.8 Exercises; Chapter 3. Complexity of Classical Planning; 3.1 Introduction; 3.2 Preliminaries; 3.3 Decidability and Undecidability Results; 3.4 Complexity Results; 3.5 Limitations; 3.6 Discussion and Historical Remarks; 3.7 Exercises; Chapter 4. State-Space Planning; 4.1 Introduction; 4.2 Forward Search; 4.3 Backward Search; 4.4 The STRIPS Algorithm; 4.5 Domain-Specific State-Space Planning; 4.6 Discussion and Historical Remarks; 4.7 Exercises; Chapter 5. Plan-Space Planning; 5.1 Introduction<br>5.2 The Search Space of Partial Plans5.3 Solution Plans; 5.4 Algorithms for Plan-Space Planning; 5.5 Extensions; 5.6 Plan-Space versus State-Space Planning; 5.7 Discussion and Historical Remarks; 5.8 Exercises; Part II: Neoclassical Planning; Chapter 6. Planning-Graph Techniques; 6.1 Introduction; 6.2 Planning Graphs; 6.3 The Graphplan Planner; 6.4 |

Extensions and Improvements of Graphplan; 6.5 Discussion and Historical Remarks; 6.6 Exercises; Chapter 7. Propositional Satisfiability Techniques; 7.1 Introduction; 7.2 Planning Problems as Satisfiability Problems; 7.3 Planning by Satisfiability
7.4 Different Encodings7.5 Discussion and Historical Remarks; 7.6 Exercises; Chapter 8. Constraint Satisfaction Techniques; 8.1 Introduction; 8.2 Constraint Satisfaction Problems; 8.3 Planning Problems as CSPs; 8.4 CSP Techniques and Algorithms; 8.5 Extended CSP Models; 8.6 CSP Techniques in Planning; 8.7 Discussion and Historical Remarks; 8.8 Exercises; Part III: Heuristics and Control Strategies; Chapter 9. Heuristics in Planning; 9.1 Introduction; 9.2 Design Principle for Heuristics: Relaxation; 9.3 Heuristics for State-Space Planning; 9.4 Heuristics for Plan-Space Planning
9.5 Discussion and Historical Remarks9.6 Exercises; Chapter 10. Control Rules in Planning; 10.1 Introduction; 10.2 Simple Temporal Logic; 10.3 Progression; 10.4 Planning Procedure; 10.5 Extensions; 10.6 Extended Goals; 10.7 Discussion and Historical Remarks; 10.8 Exercises; Chapter 11. Hierarchical Task Network Planning; 11.1 Introduction; 11.2 STN Planning; 11.3 Total-Order STN Planning; 11.4 Partial-Order STN Planning; 11.5 HTN Planning; 11.6 Comparisons; 11.7 Extensions; 11.8 Extended Goals; 11.9 Discussion and Historical Remarks; 11.10 Exercises
Chapter 12. Control Strategies in Deductive Planning

Sommario/riassunto

Automated planning technology now plays a significant role in a variety of demanding applications, ranging from controlling space vehicles and robots to playing the game of bridge. These real-world applications create new opportunities for synergy between theory and practice: observing what works well in practice leads to better theories of planning, and better theories lead to better performance of practical applications. Automated Planning mirrors this dialogue by offering a comprehensive, up-to-date resource on both the theory and practice of automated planning. The book goes well b